MR302-2
Fiber Optic Incremental Encoder
OEM PCB Controller
Instruction Manual

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REV	Date	Notes
A	8/11/2014	Initial Release
B	8/21/2014	Updated to reflect changes made to the PCB. Namely a new connector and updated serial interface to RS485/RS422.
C	2/6/2015	Changed Modbus address from 0x800 to 0x400 reading model number. Updated section 3.8 Corrected pin number to 15 Corrected the description to table for cmd 0x208
D	6/1/2015	General update and reformatting Updated Specifications Updated ZAPPY® software section with interface examples
E	9/16/2015	Updated with new Camarillo address and telephone/fax numbers

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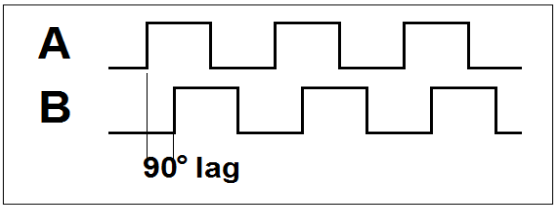
1. Product Description

1.1 Incremental Encoder Background

Incremental encoders are typically used to sense the motion and speed of a motor shaft. Typically the encoder outputs two phase-shifted signals. Depending on the direction of movement, the phase shift is either +90° or -90°, this signal is referred to as the Quadrature Signal.



Typically these encoders incorporate electronics and are susceptible to electrical interferences (EMI/RFI). Examples include:

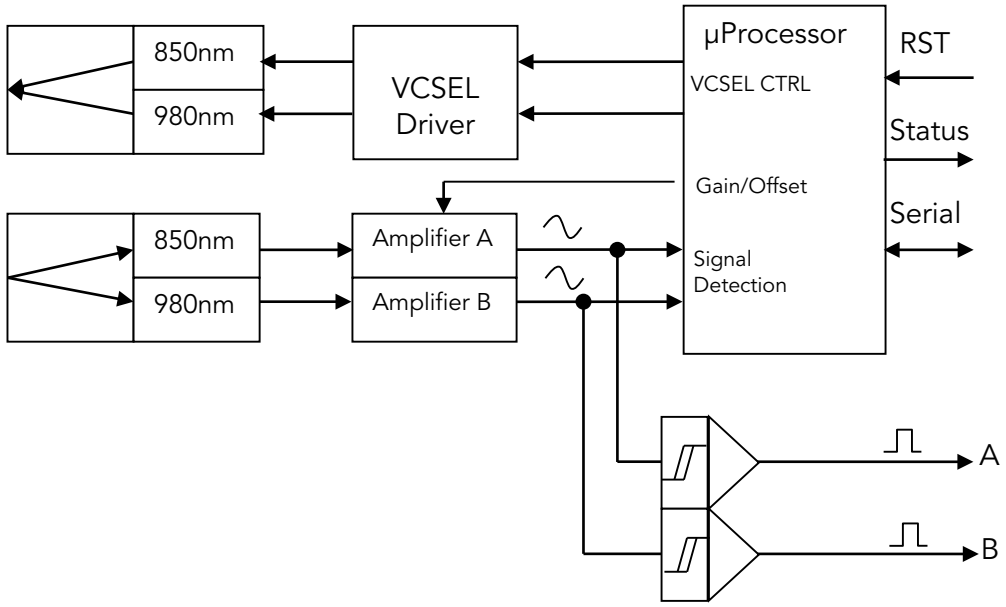
- Pipe and tube welding produces extreme interference while the welding process is active
- MRI machines operate under an extremely strong electromagnetic field
- Surgical robots must perform 100% reliably
- Aerospace actuators operate in and around other noise generating avionics

An all-optical, non-electronic passive solution such as the fiber optic encoder provides completely immunity to such interferences.

1.2 Fiber Optic Incremental Sensor

The MR302 series fiber optic position sensor system is an innovative all-optical design immune to any electro-magnetic interference such as lightning, radiation, magnetic fields and other harsh environmental conditions. The fiber optic aspect of the sensor also makes it perfectly suited for long distance speed and position sensing over hundreds of meters without being affected by ground loop problems. This innovative product can be fitted to an existing DC motor or it is available as a stand-alone encoder.

The controller board sends two separate optical wavelength signals to the encoder. The encoder then modulates each optical beam based on the direction with a leading or lagging phase shift.



The return optical signals are split up into two separate beams and converted back into an electrical signal.

A microprocessor is used to supervise the amplitude of the optical signals and constantly adjust the signal as to provide a stable quadrature output.

The microprocessor has built-in error checking and will signal any anomaly within the operation of the sensor system

2. Initial Preparation

2.1 Unpacking and Inspection

The unit was carefully inspected mechanically and electrically before shipment. When received, the shipping carton should contain the following items listed below. Account for and inspect each item before the carton is discarded.

In the event of a damaged instrument, write or call your nearest MICRONOR sales office.

Please retain the shipping container in case re-shipment is required for any reason.

2.2 Damage in Shipment

If you receive a damaged instrument you should:

1) Report the damage to your shipper immediately.
2) Inform MICRONOR
3) Save all shipping cartons.

Failure to follow this procedure may affect your claim for compensation.

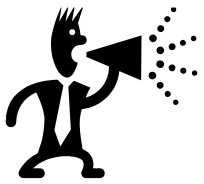
2.3 Standard Contents

MR302 Sensor:

- MR302 series sensor with fiber cable length as ordered and terminated with Duplex LC connector. Examples: MR303, MR304, etc.
- Instruction Manual (this document, one soft copy supplied with each shipment)

MR302-2 Controller PCB:

- MR302-2 Controller OEM PCB
- Instruction Manual (this document, one soft copy supplied with each shipment)



Both this Instruction Manual and ZAPPY® 302 software can also be download from www.micronor.com

3. Installation and Operation

3.1 Mounting the Sensor Unit

Various different types of sensors will work in conjunction with the MR302-2 Controller.

MR302 series Rotary Encoder offers small size and resolution up to 512ppr.

The MR303 Linear Encoder is a special read-head sensor that can be used to measure linear movement. It is constructed of both non-metallic and non-ferrous materials. The sensor is safe for use within or around MRI equipment, or within other extreme electromagnetic fields.

Figure 1. Controller works with both MR303 Linear and MR304 Rotary Encoders

When installing the sensor, be careful not to bend the fiber excessively. It is recommended to keep the minimum bend radius 25mm (1") or larger. Ensure the fiber outlet at the encoder is protected from excessive pulling or bending.

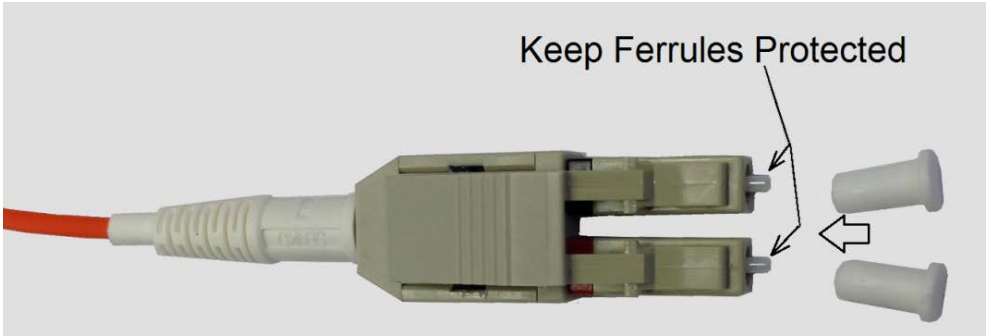


Figure 2. Keep LC Duplex connector ends protected when not in use

Make sure fiber optic connector tips are always covered when not in use. Always clean and inspect the connector ends before mating to interface.

Be sure to use proper fiber optic cleaming tools and procedures such as the Micronor MR321C Cleaning Kit. Improper tools and/or processes may damage or contaminate the optical interface.

3.2 Mounting the MR302-2 Controller PCB

The controller PCB should be mounted on 4 standoffs.
Plenty of room should be left for access to the Fiber Optic Interface.
The mounting holes are suitable for #2-56 or M2.5 screws.
The mounting holes are electrically connected to GND.
Consult Reference Drawing 98-0302-30 for more information

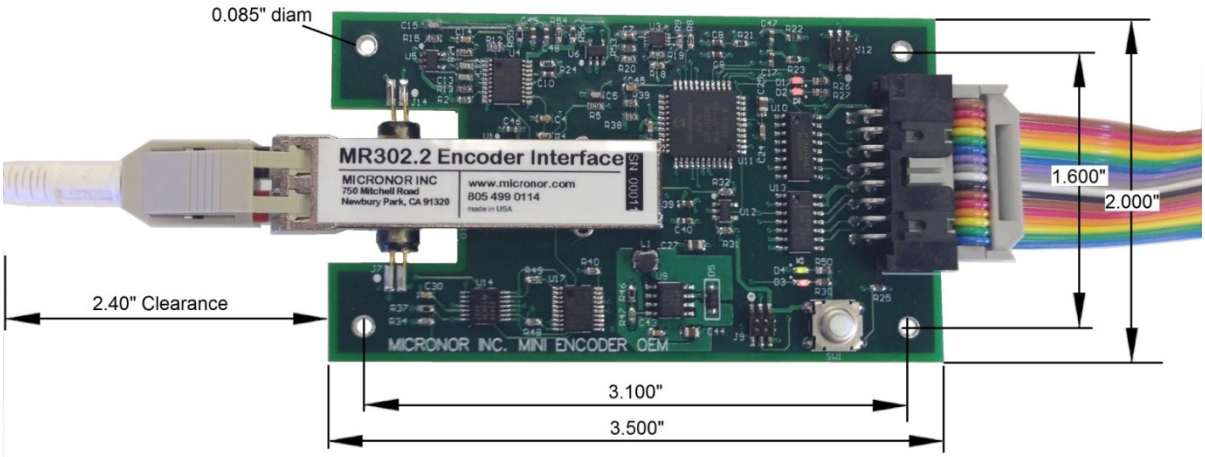


Figure 3. Dimensions of MR302-2 Controller PCB

3.3 Optical Connections to the MR302-2 Controller

A duplex fiber optic cable is used to interconnect the sensor and controller. The sensor incorporates a 1.5m optical pigtail (or as specified by customer). If a longer connection to the controller is required then an extension fiber cable having duplex LC connector may be used.

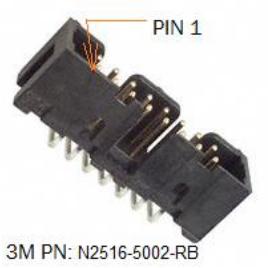
Remove the dust cap form both the connector on the cable and the receptacle on the controller. Insert the LC connector as shown. There should be a positive click when the connector is engaged properly.

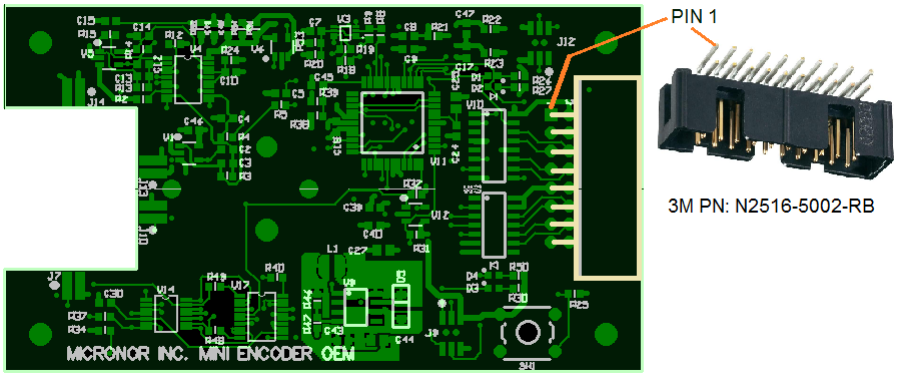
Do not force the Fiber Optic Connector!

3.4 Electrical Connections To MR302-2 Controller

The unit is powered by 5V DC with maximum 100mA current consumption.
Encoder signals are 5V RS422 Line Driver compatible.
Serial Interface is Modbus RS485/RS422 compatible.
Default baud-rate 57600, 8bit, 1 stop, no parity
Default address 235

Ribbon Connector 16 pin: 3M PN: N2516-5002-RB (Right Angle on PCB) Mating Part suggestion: 3M PN: 89116-0103			
Function	PIN	PIN	Function
n/c	1	2	+5V Power Supply
GND	3	4	n/c
ENC A-	5	6	ENC A+
ENC B-	7	8	ENC B+
+5V Power Supply	9	10	GND
(Serial) RCV-	11	12	RCV+ (Serial)
(Serial) XMT-	13	14	XMT+ (Serial)
ZERO INP	15	16	STATUS OUT (5V)

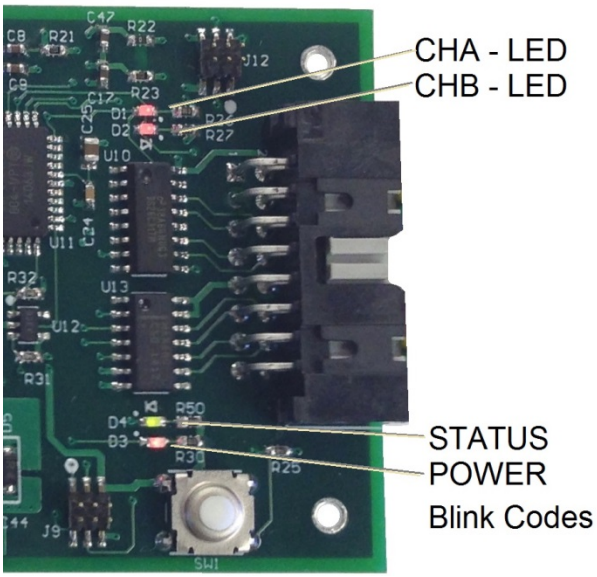




Ribbon Cable: 16 conductor 0.050" pitch
3M P/N 3302/16 300SF (Digikey P/N MC16M-10-ND)

NOTE: Mounting holes are internally connected to GND.

When all connections are made, than apply 5VDC electrical power to the controller PCB. There are 4 indicator LED's on the PCB.



The channel A & B indicator LED's are ON when the respective quadrature signal is high. When the encoder is moving, these LEDs will effectively blink.

The STATUS LED is ON when the encoder is turning.

The Power LED is ON and is steady state when the system is working properly. It indicates abnormal status using blink codes.

Blinks	Code Description
Steady ON	System is OK
1	Optical Power is too high. This is only possible when the transmitter experienced a problem. It may be possible to correct the situation by adjusting the VCSEL power using the ZAPPY® software.
2	Low optical power. When this appears, first rotate the encoder and check if the problem continues. If yes, check all optical connections. Most of the time a low power indication is the result of contaminated or bad connectors. If a very long fiber optic link is used, then the user may increase the optical power by following the initializing the power levels as described in section 3.7. (Hold down the button for 10seconds)
3	Sensor is disconnected. Broken optical link.
4	5V input power is outside safe range.
5	Internal low voltage on the 3.3V power supply.

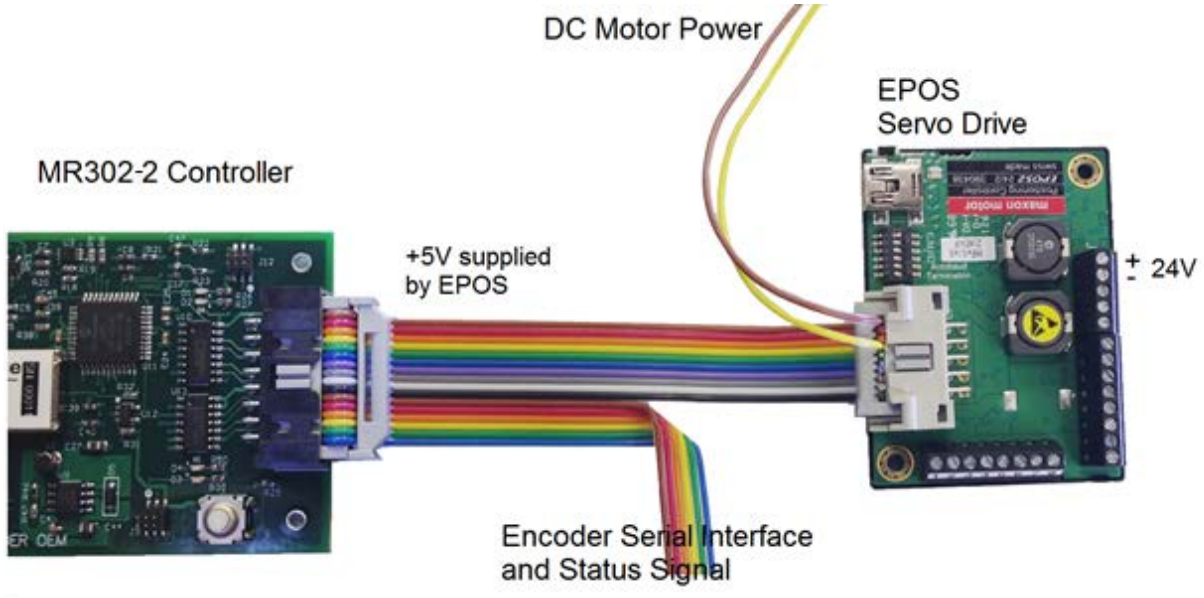
Note: The status output on J1-16 is high whenever an abnormal condition is indicated.

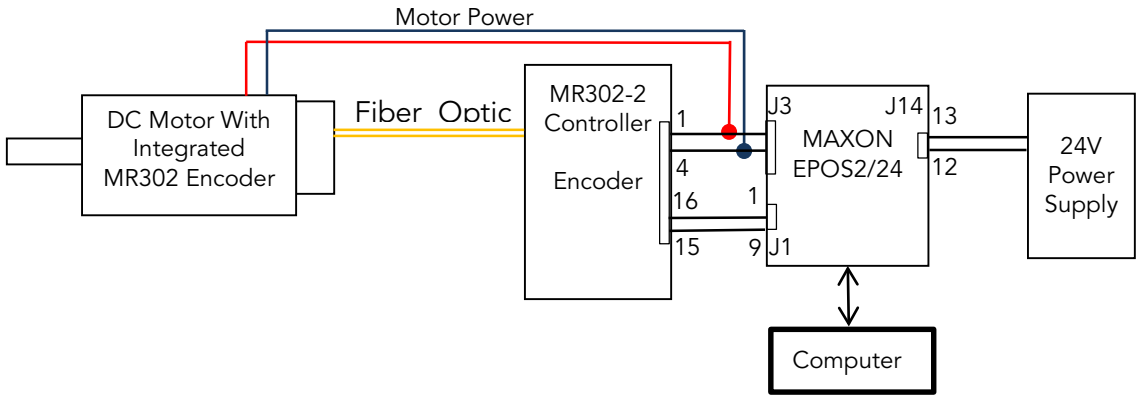
Note: There are more status conditions which are listed in Section 4.3 Error Handling. In general, any status indication is also available via serial interface.

3.5 Interfacing with a Motor Servo Drive

One common application for any encoder is to provide position and velocity information to a servo drive. To simplify the connection task, the ribbon connector pin-out of the MR302-2 Controller board is designed to directly interface with the Maxon EPOS2/24 controller.

The 5V power is derived from the EPPOS drive and the A & B line driver signals are routed from the MR302-2 controller directly to the EPOS drive on connector J3. The pins for the motor voltage output are not connected on the MR302-2 Controller PCB and thus do need to be isolated.



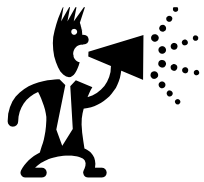


Optionally, the STATUS OUT output and ZERO INP input can be connected to the universal digital in/out of the EPOS drive. This allows the encoder STATUS output to be read into the host computer and analyzed. For automatic optical calibration, the ZERO input can be activated by outputting a logic high on the respective EPOS digital output. A typical start-up procedure would be to let DC Motor run in current mode without feedback, and then, raise Pin 15 for ~100ms. That will initiate an optical calibration cycle.

Although it is possible to read speed and position directly from the MR302-2 Controller during normal operation, this may not be necessary if the encoder information can be read directly via the servo drive system (such as Maxon EPOS23/24).

3.6 Film Mounting/Film Handling When Using MR303

Although the film positioning within the sensor slit is not critical, it should be mounted in such a way that it is as parallel to the sensor pick-up head as possible. Ideally the film should be mounted so it is perpendicular to the sensor head and always lay against one side of the slit. The film should be prevented from wobbling within the slit.



Emulsion side of film must face side where the fiber enters the sensor.

Be careful when handling film to not leave fingerprints.

After film strip is inserted into sensor, either use the supplied clip or cover to secure film and maintain proper alignment.

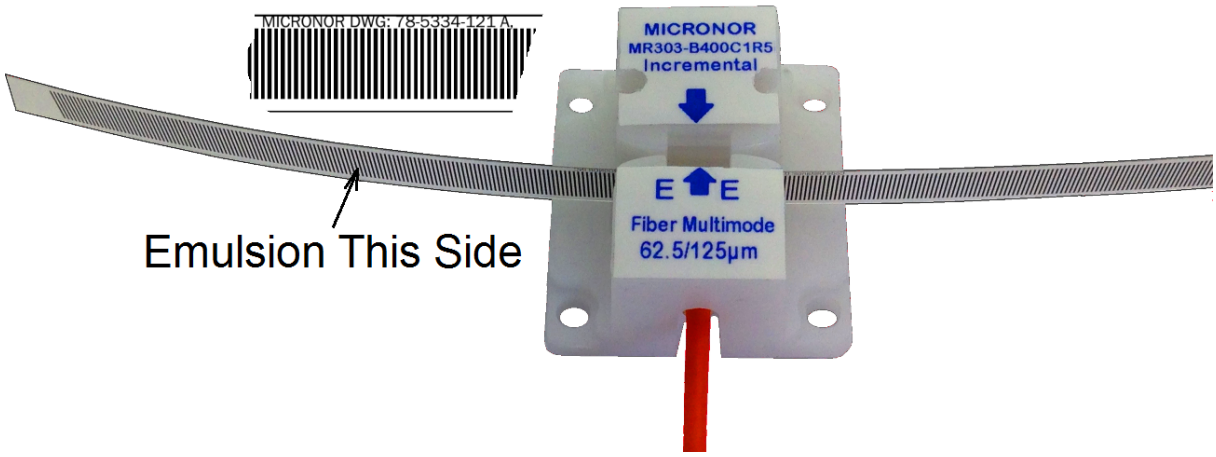


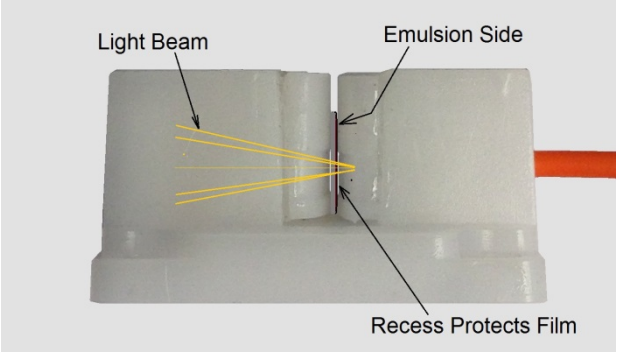
Figure 4. Positioning film inside MR303 sensor

Figure 5. The emulsion side is up when right side reading text

To protect the film from scratches where the light senses the lines, the assembly has a slight recess. It is therefore important that the film is operated sliding at the bottom of the assembly.

The high precision optical read head is very high precision and is sensitive to scratches or dust on the film. Scratches of 50µm or more can cause an erroneous pulse.

Positioning the film affects the ultimate performance of the system. Apply just enough pull to the film so as it is stretched at all times. Too much pull will increase pressure on the read surface and may lead to high wear of the film. Typically 50-100 grams of pull force is sufficient.



When using a film with 0.4mm line spacing, it is posible to obtain 0.1mm resolution. Consult Figure 6 below for recommended film strip dimensions. Each opaque and translucent cycle will need to be a total of 400µm.

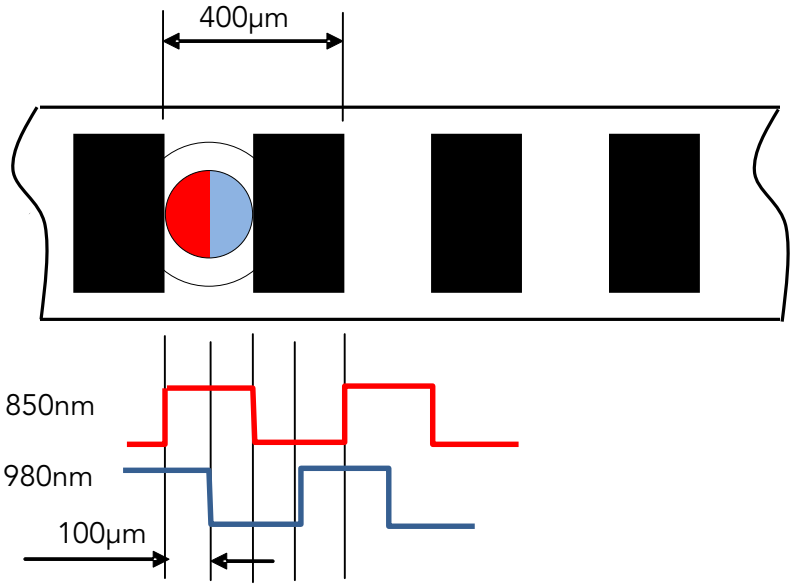


Figure 6. Filmstrip dimensions

As can be seen in Figure 6, positional accuracy is given by the film itself and the shape of the light beam. The film is made accurately to within ±3µm. The absolute edge accuracy is approx. ±25% of the slit width. With the design, as shown above, the very worst case deviation is ±50µm maximum. Typically ±25µm can be expected.

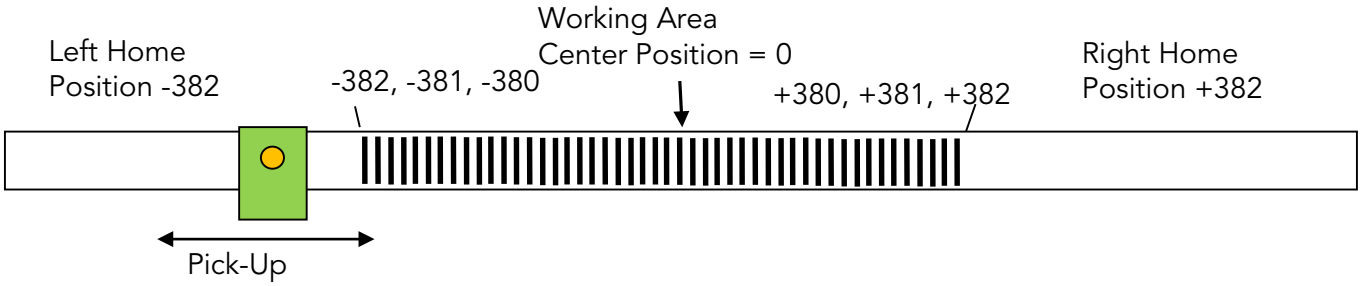
Thermal expansion of the film tape is typically 22µm/m/°C. With the temperature variation within an MRI environment being minimal, this deviation is not a factor in accuracy when operating at normal room temperature. The film base material is highly stable.

To obtain a balanced signal with a duty cycle of 50% and a phase shift of 90°, the distance from the optical fiber to the film must be accurately controlled within the pick-up assembly. This is a factory-only adjustment.

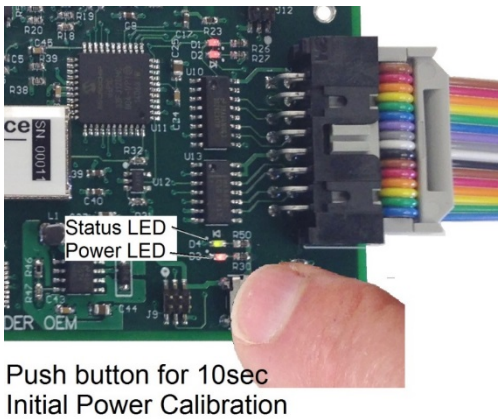
3.7 Initial Optical Power Level Referencing when using Film

After initial installation, it is important that the optical power levels (one level for each quadrature channel) are calibrated to the nominal operating level. This is required to compensate for fiber optic connector losses and variation between sensors and controllers. The MR302-2 controller is designed to perform this calibration procedure automatically once initiated by the user.

- Install the sensor, film, the controller and make all fiber connections.
- Set the sensor to a clear area of the film where there are no obstructions.
- Press the "CAL" button on the controller for 10 seconds. The PWR LED will blink while the calibration is being performed. After ~10 seconds, the STATUS LED will blink shortly, then release the button.



The internal procedure within the controller is as follows: The input amplifiers are being set to a known sensitivity (gain), then the laser power for each channel is adjusted until the desired internal voltage level (2V) is reached. The new power setting values are saved in EEPROM. This is the only procedure that will alter the laser power levels. During normal operation, only the input amplifier gain is adjusted for maintaining proper voltage levels.



NOTE: This calibration sequence may also be initiated via Modbus command.

Figure 7. Location of pushbutton for initial optical level calibration

3.8 Power-up or Periodic Optical Sensitivity Calibration

As part of the normal power-up procedure, it is possible to perform an optical power calibration. This is useful so that the system immediately starts counting with the highest accuracy. The external ZERO input (J1-Pin 15) of the controller is configured in such a way that when a +5V signal is applied to this input, the internal counter is Reset to the Preset value stored in Register 0x209. If so configured as described herein, the input amplifier level calibration may be initiated at the same time.

3.8.1 Optical sensistivity calibration for linear sensors

At power up, it is recommended to move the MR303 sensor head to a clear area of the film strip and then initiate a +5V logic pulse of ~100ms to 1sec duration to the Zero input (J1-Pin 15).

Instead of a +5V logic pulse on J1-15, the sequence may be initiated using Modbus FC05 0x007.

Register 0x208 must be configured to 0x03 in order for the above procedure to work properly.

This procedure can also be repeated at periodic interval or during self-test cycles.

3.8.2 Optical sensititivty calibration for rotary sensors

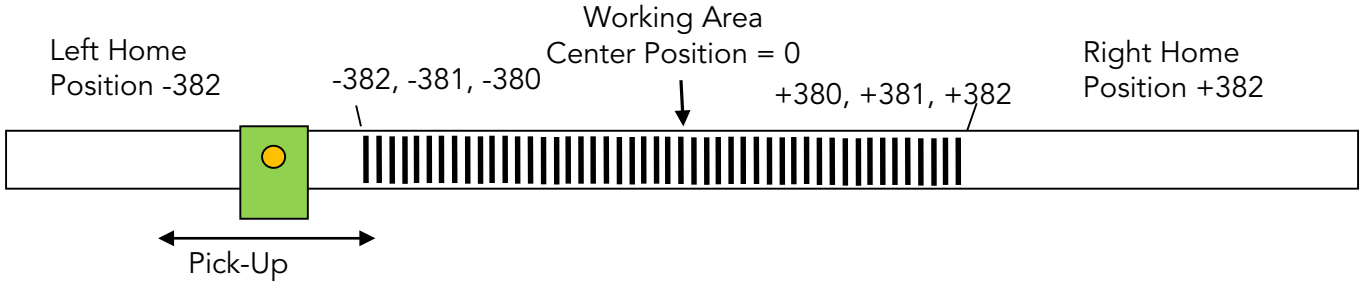
For MR30X series rotary sensors, optical sensitivity calibration is performed in real-time when the encoder is rotating. The controller monitors the signal lows and highs and sets the internal gain accordingly. Therefore, no special calibration procedure is required for rotary sensor.

3.9 Indexing for Linear Absolute Position

The MR303 linear sensor system is an incremental encoder and will not know the absolute position when the unit is powered up. Generally, an index point must be provided to obtain absolute position.

Since the MR303 fiber optic sensor works different from standard encoders, it is possible to reserve a "homing" area on the film strip. Outside the actual work area, the film is left transparent without alternating lines.

After the robot powers up, the servo system must drive the sensor head either left or right to the clear "homing" area until encoder pulses are no longer received. Tthe desired Preset reference count, corresponding to the absolute known position to the start of the first line, is loaded into the position counter. The servo motor then drives towards the start of the working area. The position counter will start counting as soon as the first line is encountered.



Note: The number examples above are when x2 multiplier is used.

The left and right homing positions are provided to the servo control system as part of an initial factory calibration cycle.

Whenever there is opportunity to position the sensor to an area outside the working area and perform a "homing" procedure, the above described scheme is elegant and does not add complexity or cost to the system.

This procedure can also be combined with an optical input sensitivity calibration sequence per Section 3.8.

3.10 Initial System Configuration and Power-Up Examples

This section provides examples on how the encoder system can be initially configured and operated. The three scenarios described are:

- Rotary encoder
- Linear Encoder using Film With HOMING Region
- Linear Encoder using Filem without HOMING Region

Micronor supplies ZAPPY® 302 software free-of-charge to MR30X users. The software is designed for configuring and troubleshooting an MR30X rotary or linear encoder system. The ZAPPY® screens and command buttons emulate the Modbus commands so that the user can become familiar with configuring and operating the system.

For detailed information about specific Modbus commands, consult Section 7.

3.10.1 Rotary Encoder Configuration and Operation

Hardware Example: MR304 Rotary Encoder and MR302-2 Controller

For Rotary Applications Using Quadrature Outputs Only

For systems that will use the A/B quadrature outputs only, the user need only optically connect the encoder to the controller and go. Optical Signal Calibration occurs automatically while the encoder is turning.

Before initial use, it is recommended to connect the optical link (all segments, full length) first and perform an Optical Signal Calibration. This is to make sure that the optical link loss bidget is within specifications.

Initial Configuration Sequence Rotary Encoder using Quadrature Outputs Only		
Step	Action	Notes
1	Connect	Connect encoder and controller with final optical link connected (all segments).
2	Optical Calibration	Perform an Optical Signal Calibration by simultaneously rotating the encoder and holding down the on-board Calibration pushbutton for at least 10 seconds. The POWER LED will blink while calibration is performed. After 10 seconds,the STATUS LED will blink shortly indicating that calibration is complete and the user can then release the button.
3	Ready To Use	

Power-Up Sequence Rotary Encoder using Quadrature Outputs Only		
Step	Action	Notes
1	System ready to operate	

For Rotary Speed/Position Sensing Applications Using Modbus Interface

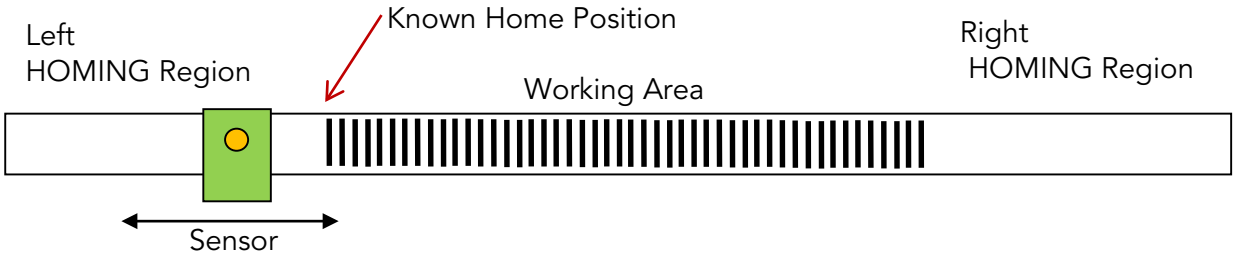
Many integrated OEM systems will want to take advantage of the embedded functions within the MR302-2 controller for reading rotary encoder speed and position via the Modbus interface. This frees the controller or PLC from tracking these parameters themselves via the quadrature outputs.

Initial Configuration Sequence Rotary Encoder using Modbus communincations			
Step	Command Name	Register Address	Notes
1	Reset Mode	FC10 0x208	Set to 1 to reset Position Counter to the Preset Value. For the Position Counter to function properly, the user's actuator will need to be in the desired reference position when the ZERO Input is pulsed.
2	Preset Value	FC10 0x20A	This will be the Position Counter value when the user's actuator system is in the reference position. Typically the user will set this value to 0 unless another initial setting is required.
3	Quadrature Multiplier	FC10 0x211	Set to 0 for 2 counts per line Set to 1 for 4 counts per line
4	Direction	FC10 0x20B	With this command, the user can set the preferred direction and "polarity" of the Position Counter. Set to 0=CW or 1=CCW.
5	Speed Filter	FC10 0x216	For applications monitoring Speed via Modbus, the user may want to select a value (0-8) to filter speed results.
6	Save To EEPROM	FC05 0x002	Send this command to save all current parameters to internal EEPROM

Power-Up Sequence Rotary Encoder using Modbus communications			
Step	Command Name	Action	Notes
1	User actuator system is at initial reference position.		
2	ZERO Input	Pulse ZERO Input or send FC05 0x007 command	With Reset Mode 0x208 set to 1, the controller will reset Position Counter to the Preset Value. ZERO Input may also be a homing switch.
3	System ready. Read Position Count and Speed via Modbus		

3.10.2 Linear Encoder With Film And Using HOMING Function

Hardware Example: MR303 Linear Encoder, MR302-2 Controller and TD5334 series Film Strip with 1 or 2 HOMING regions. The diagram below illustrates an application employing a Film Strip with HOMING region on both sides.



Section 3.9 described how to using the HOME technique as an Index for absolute position monitoring. This type of application would then use the Modbus interface to read absolute position and speed status. The quadrature outputs can also be used independently.

The following tables describe how to initially configure and operate the MR303 system in this scenario.

Initial Configuration Sequence HOMING Linear Encoder Configuration			
Step	**Command Name**	**Register Address**	**Notes**
1	Reset Mode	FC10 0x208	Set to 3 to perform both an Optical Signal Calibration and reset Position Counter at the same time. For the Position Counter to function properly, the user's actuator will need to be in the "Homing" zone when the ZERO Input is pulsed.
2	Preset Value	FC10 0x20A	This will be the Position Counter's initial value when the user's actuator system moves out of the HOMING region and encounters the first line on the Encoder Film Strip. Typically user will set this value to 0 unless another intial setting is required.
3	Quadrature Multiplier	FC10 0x211	Set to 0 for 2 counts per line Set to 1 for 4 counts per line
4	Direction	FC10 0x20B	With this command, the user can set the preferred direction and "polarity" of the Position Counter. Set to 0=CW or 1=CCW.
5	Speed Filter	FC10 0x216	For applications monitoring Speed via Modbus, the user may want to select a value (0-8) to filter speed results.
6	Save To EEPROM	FC05 0x002	Send this command to save all current parameters to internal EEPROM

Example:
To perform the optical calibration using the external pin and set the counter to a predefined value, and set the turn direction to 1 t the initial setup should be as follows:

Register 0x0001 "xxxx" Counter Register may be any value
Register 0x0208 "3" Reset Mode
Register 0x0209 "250" Preset Register. This value will be in the counter after the reset
Register 0x020B "1" Turn or Count Direction
Execute FC05-2 to save the parameters in EEPROM

After a normal power up, all is required to drive the sensor to the transparent area of the film and pulse the External Homing input.

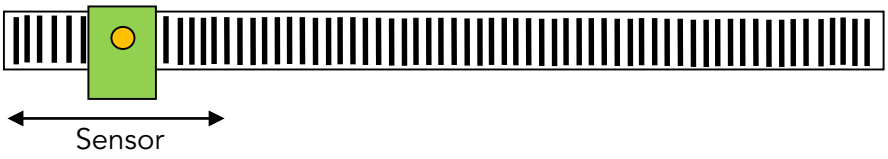
Register 0x0001 "250" Counter Register is now set at 250
Register 0x0208 "3" Reset Mode
Register 0x0209 "250" Preset Register. This value will be in the counter after the reset
Register 0x020B "1" Turn or Count Direction

Note: Executing the calibration will automatically save all current parameter register content to EEPROM.

Normal Power-Up Sequence HOMING Linear Encoder			
Step	Command Name	Action	Notes
1	User actuator system within HOMING region.		
2	ZERO Input	Pulse ZERO Input or send FC05 0x007 command	With Reset Mode 0x209=3, controller will perform Optical Signal Calibration and reset Position Counter to the Preset Value.
3	System ready. Read Position Count and Speed via Modbus. It is recommended to initiate the aabove procedure at any time that the sensor is known to be in the HOMING region. Quadrature outputs can also be used independently.		

3.10.3 Linear Encoder With Film Without HOMING Region

Hardware Example: MR303 Linear Encoder, MR302-2 Controller and TD5334 series Film Strip without HOMING region. The diagram below illustrates an application employing a Film Strip without any HOMING region.



In this section, the MR303 linear encoder uses an Encoder Film Strip without a HOMING region. That is, the Encoder Film Strip is a sequence of lines only. A typical application will use the Modbus interface to track position and speed. The quadrature outputs can also be used independently.

The following tables describe how to initially configure and operate the MR303 system in this scenario.

Initial Configuration Sequence Non-HOMING Linear Encoder			
Step	Command Name	Register Address	Notes
1	Reset Mode	FC10 0x208	Set to 1 to reset Position Counter only. For the Position Counter to function properly, user's actuator must be at the reference position when ZERO Input is pulsed.
2	Preset Value	FC10 0x20A	This will be the Position Counter value when the actuator is at the reference position. Typically, the user will set this value to 0 unless another initial setting is required.
3	Quadrature Multiplier	FC10 0x211	Set to 0 for 2 counts per line Set to 1 for 4 counts per line
4	Direction	FC10 0x20B	With this command, the user can set the preferred direction of the Position Counter. Set to 0=CW or 1=CCW.
5	Speed Filter	FC10 0x216	For applications monitoring Speed via Modbus, the user may want to select a value (0-8) to filter speed results.
6	Save To EEPROM	FC05 0x002	Send this command to save all current parameters to internal EEPROM
7	Optical Calibration		Perform an Optical Signal Calibration by simultaneously moving the Encoder Film Strip back and forth while holding down the on-board Calibration pushbutton for at least 10 seconds. The POWER LED will blink while calibration is performed. After 10 seconds,the STATUS LED will blink shortly indicating that calibration is complete and the user can then release the button.

Power-Up Sequence Non-HOMING Linear Encoder			
Step	Command Name	Action	Notes
1	User actuator system is at initial reference position.		
2	ZERO Input	Pulse ZERO Input or send FC05 0x007 command	Controller will reset Position Counter to the Preset Value.
3	System ready. Read Position Count and Speed via Modbus Quadrature outputs can also be used independently.		
4	An automatic Optical Calibration is performed whenever the sensor sweeps through the active area at minimum speed of 0.2 meters/second.		

4. Modbus Serial Communications

4.1 Modbus Serial Interface

The main purpose of the Modbus-compatible serial interface is to query the MR302-2 controller for status, position and speed while in operation. The serial interface is also used to configure the controller unit as well as system troubleshooting.

MICRONOR supplies the ZAPPY® software to access these functions via the serial interface of your PC (Personal Computer) computer.

Serial Interface Specification (default)

- Serial with logic levels full duplex.
- Baudrate programmable: 57,600 baud
- 1 Start Bit
- 8 Data Bits
- 1 Stop Bit
- no parity

The protocol is Modbus compatible and thus the protocol includes a node address. That is so that the PCB could be integrated into larger systems using a number of Modbus slaves. Factory Standard ModBus Address is set to 235 (Hexadecimal 0xEB).

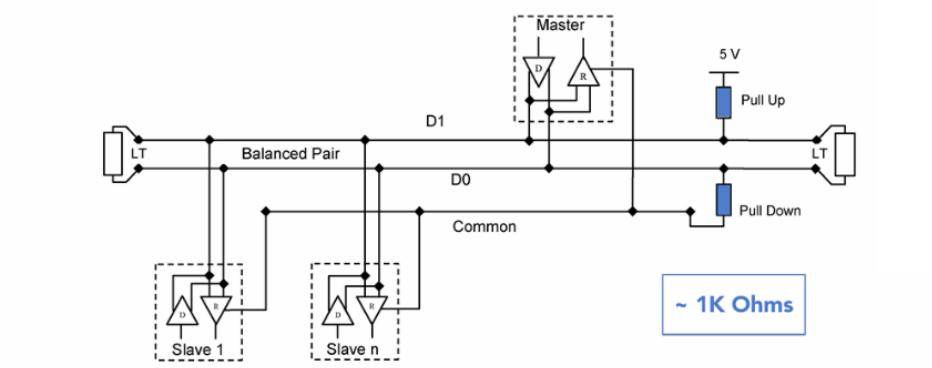
Note: The MR302-2 OEM PCB requires a RS485/422-to-RS232 adaptor or RS485/422-to-USB adaptor for communicating with a computer.

Note: The MR302-2 OEM Controller uses the 235 address as the common call address. It will always respond to address 235.

Pull-Up/Pull-Down Resistors

Since the bus lines will go idle and into an undefined state when inactive, it is important that the lines are pulled-up and pulled-down respectively when inactive.

The pull-up / pull-down resistor are typically at the master. Consult following Modbus circuit definitions.



2W-MODBUS Circuits Definition

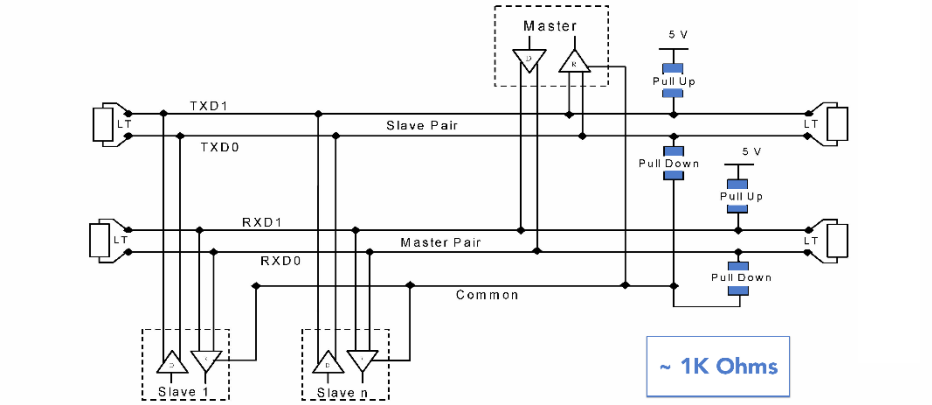
Required Circuits on ITr	Required Circuits on IDv	For device	Required on device	EIA/TIA-485 name	Description
D1	D1	I/O	X	B/B'	**Transceiver terminal 1, V1 Voltage** (V1 > V0 for binary 1 [OFF] state)
D0	D0	I/O	X	A/A'	**Transceiver terminal 0, V0 Voltage** (V0 > V1 for binary 0 [ON] state)
Common	Common	--	X	C/C'	Signal and optional Power Supply Common

2-Wire Circuit Half Duplex

D1 (RX+ / TX+) is pulled up to +5V

D0 (RX- / TX-) is pulled down to GND

Recommended resistor is 1KΩ



4W-MODBUS Circuits Definition

Required Circuits on ITr	Required Circuits on IDv	For device	Required on device	EIA/TIA-485 name	Description for IDv
TXD1	TXD1	Out	X	B	**Generator terminal 1,** Vb Voltage (Vb > Va for binary 1 [OFF] state)
TXD0	TXD0	Out	X	A	**Generator terminal 0**, Va Voltage (Va > Vb for binary 0 [ON] state)
RXD1	RXD1	In	**(1)**	B'	**Receiver terminal 1**, Vb' Voltage (Vb' > Va' for binary 1 [OFF] state)
RXD0	RXD0	In	**(1)**	A'	**Receiver terminal 0**, Va' Voltage (Va' > Vb' for binary 0 [ON] state)
Common	Common	--	X	C/C'	Signal and optional Power Supply **Common**

4-Wire Circuit Full Duplex

TXD1 (TX+) and RXD1 (Rx+) are pulled up to +5V

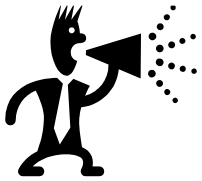
TXD0 (TX-) and RXD0 (RX-) are pulled down to GND

Recommended resistor is 1KΩ

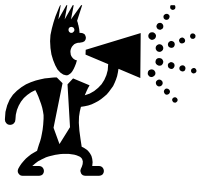
4.2 MODBUS Communications Protocol

The communications protocol follows the Modbus RTU (binary) protocol. A number of commands allow for configuring the operational parameters of the MR302 while other commands are specifically meant for diagnostics used during setup, maintenance and troubleshooting. The status and position readout registers are intentionally arranged in sequence for a quick readout while system is in operation mode. The format for the commands and responses in general follow the MODBUS RTU specification, with the exception that not all registers maybe combined within one readout sequence. See table below for allowable register combination.

➔ Modbus information can be obtained at www.modbus.com



What Is ZAPPY® Setup Software?
Zappy® 302 is a setup program provided free-of-charge with the purchase of the MR302 system. ZAPPY® runs on Windows XP, Vista, Windows 7, Windows 8 and requires .net Framework 4.0 to be on the machine. Please refer to section 7 for detailed information.



Unless you plan to connect the MR302 to your own PLC or computer equipment for real-time data retrieval, you do not need to become familiar with the detailed communications protocol described herein.

Framing

Message frames are separated by a silent interval of at least 3.5 character times. If a silent interval of more than 1.5 character times occurs between two characters of the message frame, the message frame is considered incomplete and is discarded.
A 16bit LRC/CRC Frame Check follows the message.

Device Address Selection

The MR302 comes pre-configured with Device address 235 (Broadcast address).
The MR302 always listens to address 235 (Broadcast Address). To re-program the device address, send desired new address via command FC10 to register 0x104 via the broadcast address (235) and then send the appropriate "STORE EEPROM" command via FC52 register Upon that procedure the unit will listen to both the newly assigned Device Address ***and*** the Broadcast address 235.

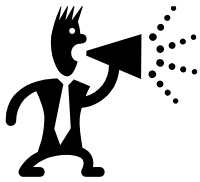
Register Numbers versus Meter Addresses

In this instruction manual, all registers are referred to by their address, i.e. starting at 0.

Some Master devices (e.g., Modicon) require that the desired Register Number and not the Register Address be entered. The Register Number is 1 higher than the Register Address. For entry to these devices, add 1 to the Register Address shown in the tables below. The Register Address shown will then be output from these devices.

FUNCTION FC03 – Read Holding Registers
FUNCTION FC10 – Write Holding Registers

Holding registers FC03 are used for reading the position and all other parameters
These Registers can be written using Function FC10 using identical address offset



Be cautious of using the Operating Mode 0x105 register command. Do not put unit in any of these modes without first consulting the user manual. Be familiar with what these functions before using.

Register Address	Register Number	Name	# regs	Range	Description
0x000	0x001	System Status	1	n/a	Returns the system status. A 0x0000 means all is ok. See status information.
0x001	0x002	Get Encoder Count	2	n/a	Returns or sets position count as a 32-bit integer.
0x003	0x004	Get Speed	2	n/a	Returns the speed information as a 32 –bit signed in 1/100 rpm.
0x004	0x005	reserved	2	n/a	
0x040	0x041	Get Error Counts	18	n/a	Returns 18 registers with the total number of errors for each error class.
0x100	0x101	reserved	2	0 - MaxCount	
0x104	0x105	Device Address	1	1 – 254	Sets the MR302 serial address for commands. Note that the address 4 cannot be used. A FC06 command to save EEPROM must be issued following this command.
0x105	0x106	Operating Mode	1	0, 2	Used to setting MR302 in calibration, or troubleshooting mode. Normal Operating is 0. Debug mode is 2. Do not put unit in any of these modes without first consulting the user manual. Be familiar with what these functions before using.

0x130	0x131	CHA Amplitude minimum	1	n/a	Outputs the minimum observed amplitude of the optical signal. Generally this signal is less than 15 counts because the optical signal should swing from 0 to 640counts. (0V to 2V). Of course the encoder must be turning otherwise the signal can be anything from 0 to +640.
0x131	0x132	CHA Amplitude maximum	1	n/a	Outputs the maximum observed amplitude of the optical signal. Generally this is signal approximately 640 counts because the optical signal should swing from 0 to 640counts. (0V to 2V). Of course the encoder must be turning otherwise the signal can be anything from 0 to +640.
0x132	0x133	Voltage Offset Factory Calibration	1	-128 – 127	Factory use only – do NOT write to it. Hardware calibration value for voltage output
0x133	0x134	Voltage Gain Pos Factory Calibration	1	-128 – 127	Factory use only – do NOT write to it. Hardware calibration value for voltage output
0x134	0x135	Voltage Gain Neg Factory Calibration	1	--128 – 127	Factory use only – do NOT write to it. Hardware calibration value for voltage output
0x135	0x136	Current Gain Factory Calibration	1	-128 – 127	Factory use only – do NOT write to it. Hardware calibration value for current output
0x136	0x137	CHB Amplitude minimum	1	n/a	Outputs the minimum observed amplitude of the optical signal. Generally this signal is less than 15 counts because the optical signal should swing from 0 to 640counts. (0V to 2V). Of course the encoder must be turning otherwise the signal can be anything from 0 to +640.
0x137	0x138	CHB Amplitude maximum	1	n/a	Outputs the maximum observed amplitude of the optical signal. Generally this signal is approximately 640 counts because the optical signal should swing from 0 to 640counts. (0V to 2V).

					Of course the encoder must be turning otherwise the signal can be anything from 0 to +640.
0x138	0x139	VCSEL Control	1	0 - 3	Factory use only – do NOT write to it. Used to turn OFF the optical output for each channel. ➔ 1 = CHA ➔ 2 = CHB ➔ 3 = Both
0x139	0x13A	Baudrate Serial Communications	1	0 – 3	Sets the Baudrate for Serial Communications on the MODBUS. 0 = 9,600 1 = 19,200 2= 38,400 3 = 57,600 4 = 115,200
0x13A	0x13B	Internal 3.3V value	1	n/a	Gets the internal voltage in 10mV increments.
0x13B	0x13C	Power Supply 5V	1	n/a	Gets the 5V power supply voltage in 10mV increments.
0x13C	0x13D	reserved	1	n/a	
0x13D	0x13E	reserved	1	n/a	
0x13E	0x13F	reserved	1	n/a	
0x140	0x141	Amplifier Gain CHA	1	0 – 255	Controls the gain of Channel A amplifier. 0 is max gain, 255 is minimum gain
0x141	0x142	Amplifier Offset CHA	1	0 – 255	Controls the input offset of Channel A amplifier. This is set at the factory only. Should typically be a low number of less than 20.
0x142	0x143	Amplifier Gain CHB	1	0 – 255	Controls the gain of Channel B amplifier. 0 is max gain, 255 is minimum gain
0x143	0x144	Amplifier Offset CHB	1	0 – 255	Controls the input offset of Channel B amplifier. This is set at the factory only. Should typically be a low number of less than 20.
0x144	0x145	Optical output Power for CHA	1	0 – 255	Controls the output power of CHA. 0 is minimum power, 255 is maximum power. It is used to balance each VCSEL diode. Power output may also be increased to compensate for long fiber optic link losses.
0x145	0x144	Optical output Power for CHB	1	0 – 255	Controls the output power of CHB.

					0 is minimum power, 255 is maximum power. It is used to balance each VCSEL diode. Power output may also be increased to compensate for long fiber optic link losses.
0x200	0x201	Voltage Mode	1	0 - 3	Defines the output mode for the voltage output. 0 = OFF no Position Output **Not implemented**
0x201	0x202	Voltage Scale	2	0 – MaxCount	Establishes the scale used for the voltage output. Regardless of Voltage Mode setting 10V refers to the scale value. When the position count reaches the scale value the output is 10V. **Not implemented**
0x203	0x204	Voltage Filter	1	0 – 15	Sets the low pass filter for the voltage output. **Not implemented**
0x204	0x205	Current Mode	1	0 – 2	Defines the output mode for the current output. 0 = OFF current is < 300uA. **Not implemented**
0x205	0x206	Current Scale	2	0 – MaxCount	Establishes the scale used for the isolated current output. Regardless of current Mode setting 16mA refers to the scale value. When position count reaches the scale value then the output is 16mA plus 4mA bias for a total of 20mA. **Not implemented**
0x207	0x208	Current Filter	1	0 – 15	Sets the low pass filter for the current output. **Not implemented**
0x208	0x209	Reset Mode	1	0 – 4	Defines how the hardware ZERO input resets the internal counter. 0 = No action when external input is high. 1 = Resets the Position Counter. 2 = Initiate an Optical Calibration when high 4 = Initiate an Laser Calibration when high The above bit positions may be combined. Example:

					3 = Resets Position Counter ***and*** initiates an Optical Calibration Cycle. This is useful when using film strip with clear homing area.
0x209	0x20A	Preset Value	2	0 - MaxCount	Counter will be preset to this value when the Zero push button is pressed or when hardware input is activated. (See Reset Mode)
0x20B	0x20C	Direction	1	0 - 1	Defines output results based on turning direction of the sensor 0 = when CW outputs are positive reading. 1 = when CCW then outputs are positive reading
0x211	0x212	Quadrature Signal Multiplier	1	0,1	0 = counts cycles x2 1 = counts cycles x4
0x214	0x213	Quadrature Voltage	1	0,1	Set the line driver output voltage 0 = disabled 1 = 5V 2 = 12V 3 = 24V **Not implemented**
0x215	0x216	Analog Output Select	1	0,1	Select voltage or current output 0 = Voltage 1 = Current (4-20mA with 3mA overrange) **Not implemented.**
0x216	0x217	Speed Filter	1	0 – 8	Sets the speed filter. Applies to ModBus and USB output. The higher the number the stronger the filter effect. 0 disables the filter.
0x230	0x231	Set Point 1 On	2	0 - MaxCount	Lower threshold for digital limit switch output 1
0x232	0x233	Set Point 1 Off	2	0 - MaxCount	Upper threshold for digital limit switch output 1
0x234	0x235	Set Point 2 On	2	0 - MaxCount	Lower threshold for digital limit switch output 2
0x236	0x237	Set Point 2 Off	2	0 - MaxCount	Upper threshold for digital limit switch output 2
0x238	0x239	Talker Rate/Mode	1	0 - 4095	Directs the unit to output the position or speed at the pre-programmed interval. **Not implemented**
0x300	0x301	CHA minimum	1	n/a	engineering measurement output
0x301	0x302	CHA maximum	1	n/a	engineering measurement output
0x302	0x303	CHB minimum	1	n/a	engineering measurement output
0x303	0x304	CHB maximum	1	n/a	engineering measurement output

0x304	0x305	n/a	1	n/a	engineering measurement output
0x305	0x306	n/a		n/a	
0x306	0x307	n/a		n/a	
0x307	0x308	n/a		n/a	
0x330	0x331	POT 1A	1	0 - 255	Pot U4A (CHA offset) (ENGWRT only)
0x331	0x332	POT 1B	1	0 - 255	Pot U4B (CHA gain) (ENGWRT only)
0x332	0x333	POT 1C	1	0 - 255	Pot U4C (CHB offset) (ENGWRT only)
0x333	0x334	POT 1D	1	0 - 255	Pot U4D (CHB offset) (ENGWRT only)
0x400	0x401	Device Name	4	n/a	Returns the ASCII string equivalent as device name (MR330)
0x404	0x405	Version	4	n/a	Returns the ASCII string equivalent of the software version form MM.mm.bb
0x408	0x409	Serial Number	2	n/a	Returns the serial number of the device.

Note: MaxCount = 2^25-1 => 33,554,431

FUNCTION FC05 – Write Single Coil

Single Coil commands are used to trigger an action by sending True (0xFF)

Register Address	Register Number	Name	Description
0x001	0x002	Device Reset	Same as a Power OFF and Power ON cycle.
0x002	0x003	Save To EEPROM	Save current parameters to EEPROM. A time delay of approximately 20ms should be allowed before sending any other command.
0x003	0x004	Restore From EEPROM	Restore all configuration parameters from EEPROM. Same as a Power Up.
0x004	0x005	Restore Factory Defaults	Restores Factory Defaults for each user parameter. Factory calibration values and pairing data are not affected.
0x005	0x006	Clear Status	Clears the status register. If another error is pending then the status register will reflect that new value in queue.
0x006	0x007	Clear Error Count Table	Resets error table counters to 0. Same as in power up.
0x007	0x008	Emulate ZERO Input	This software emulates external ZERO input pulse whose response is determined by the Reset Mode 0x208 setting.

MODBUS Message Format

The following is a brief overview of the detailed byte by byte messaging of the ModBus protocol. Please consult the Modbus standards for more detailed information. When using appropriate drivers the user does not need to be concerned with the details as described below.

DA = Device Address
FC = Function Code
RA = Register Address
NR = Number to Read
NB = Number of bytes

DD = Data to read
WW = Data to write
SF = Sub Function
EC = Error Code

CRCL = CRC Byte low
CRCH = CRC byte high

FC	Action	Sync 3.5b	Byte Number										
			1	2	3	4	5	6	7	8	9	10	11
01 01	request response	pause	DA DA	FC FC	RA NR								
03 03	request response	pause	DA DA	FC FC	RA NB	RA DD*	NR DD*	NR CRL	CRL CRH	CRH			
04 04	request response	pause	DA DA	FC FC	RA NR								
05 05	request response	pause	DA DA	FC FC	RA RA								
08 08	request response	pause	DA DA	FC FC	SF SF								
23 23	request response	pause	DA DA	FC FC	RA NR	RA							

DD* = number of bytes requested or being sent

4.3 Error Handling and Troubleshooting

4.3.1 Explanation of Status and Error Handling

The MR302 incorporates a sophisticated integrity monitoring, error and failure reporting system. There are four Error Groups:

1. EEPROM
   At start-up the EEPROM checksum and EEPROM data integrity are checked.

2. Power Supply Voltages
   At start-up, the applied power supply voltage (+5V) and internal voltages are checked. If they fall outside the required value, errors are logged and reported.
   These voltages are evaluated once at system power-up. Subsequent voltage changes will not be evaluated.

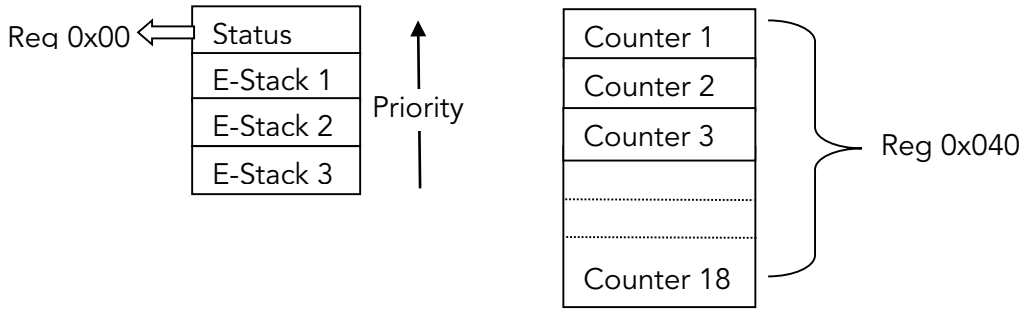
3. Sensor Read Error
   - Low optical power
   - Position read error
   - Restore value out of range

4. Communication Errors
   Communication errors are flagged by the underlying Modbus drivers. However, Modbus standard does not specify a data integrity test. This is where the MR302 allows the user to query the Status byte after each transmission to verify if the provided data was within the appropriate range, etc.

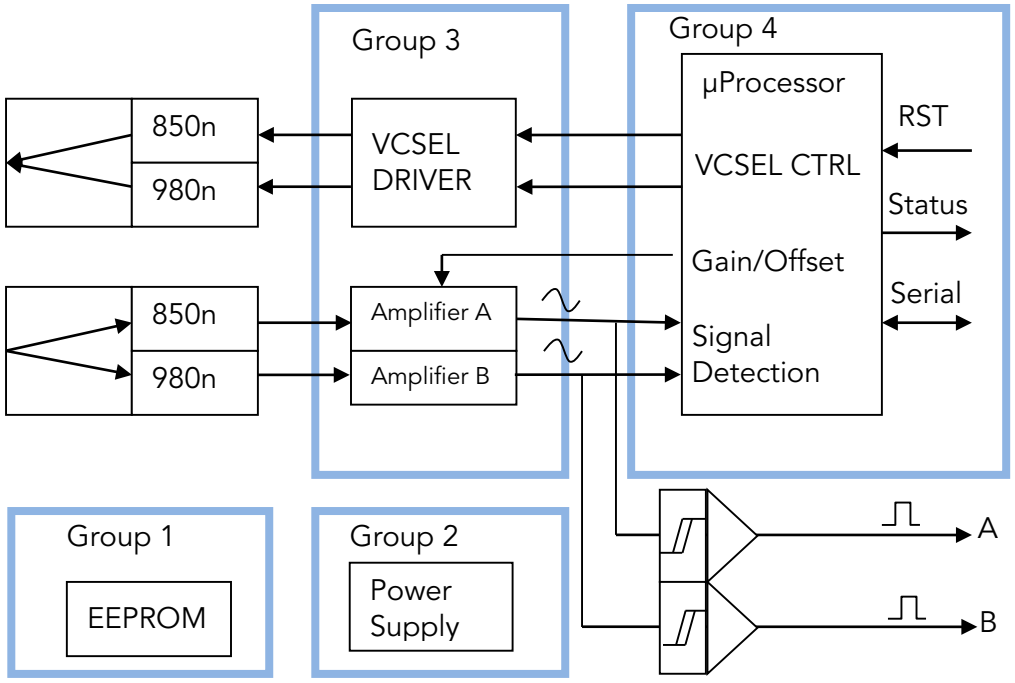
4.3.2 Explanation of Status and Error Indication

When an error occurs the System Status Word is set with the associated Error Code (Register 0x00). When more than one error at the time occurs then the error code is stacked up in order of its priority.

Each error has an associated error counter. The user may request all error registers for examination through a request to Register 0x040. MODBUS Function Register 0x40, Reads all 18 Error Registers Sequentially



Error Groups



All errors get logged but may not necessarily provide visual indication. The user should take necessary action based on the severity level of the reported status/error.

3 = System will no longer work without a remedy.
2 = Important, problem should be fixed but system may still be partially operational
1 = Benign, system keeps on working

After examination the user may clear the Error Indication by issuing the Function Call FC5 to coil number 5. This will clear the indicated error in the Status byte. If there are more errors stacked up, then the next highest priority will be displayed.

Some errors are cleared as soon as normal operation is established. For instance, when the sensor is disconnected or a high loss in the optical connection occurs, an error is reported and the PWR LED will blink. When the optical connection is re-established, then the error will clear itself without user interaction.

Some errors are not sufficient cause of a problem. They are logged and indicated by a short blink on the PWR LED and then will clear themselves. For instance, if the 5V power supply deviates by more than ±5%, an error is indicated. Since the MR302-2 works flawlessly in the range of 4.3V to 5.6V, there is no cause for further error indication.

Table 1. Error Codes

Hardware Related Status Indication EEPROM					
#	Description	S	Remedy	How Cleared	Announced
257	EEPROM INIT EEPROM is not initialized not initialized. This occurs only on first factory power up of new system or when a badly corrupt EEPROM is detected	3	Firmware automatically re-initializes the EEPROM. User must remove power and apply power again. Restore factory values. All parameters are lost.	Recycle Power	Blink 5x + code
258	EEPROM Checksum checksum failure both banks	3	Both data banks indicate a bad checksum. User should read all parameters and verify proper settings and then save parameters again using Miconor ZAPPY® software.	software or recycle Power	Blink 5x + code
259	EEPROM Checksum Low Bank checksum failure low bank	1	One set of data in EEPROM shows a bad checksum. Firmware automatically corrects the error.	n/a	n/a
260	EEPROM Checksum High Bank checksum failure low bank	1	One set of data in EEPROM shows a bad checksum. Firmware automatically corrects the error.	n/a	n/a
261	EEPROM Bad Value One or more parameter values are out of range in both data banks.	3	User should use ZAPPY® to read and examine the data and restore the corrupted value.	Timed Clear	Blink 5x + code
Voltages					
#	Description	S	Remedy	How Cleared	Announced
513	Bad Hardware No Clock Signal from CPLD Bad I2C Bus on internal components	3	Recycle Power If persist repair	next startup	Blink 5x
514	3.3V out of range	3	Check 5V input power	next startup	Blink 5x
515	5V out of range	2	Check 5V input power	next startup	Blink 4x + Code

Position Sensor Failures					
#	Description	S	Remedy	How Cleared	Announced
770	Sensor Disconnect Detect low optical power	3	Check Fiber Optic connection to the sensor. Initiate a new Sensor pairing.	self clear when restored.	Blink 3x + code
771	Sensor Low Power The fiber is connected however not enough power is being received for reliable operation.	2	this error occurs due to contaminated connectors. Or long link lengths in excess of 1.5km. Check your fiber optic link. The one way loss should be less than 5dB.	self clear examine error counter for a history of this error.	Blink 2x + code
772	Receiver gets excessive optical power	2	If this occurs the VCSEL optical power needs to be reduced. This is accomplished using ZAPPY® software. An optical attenuator could also be inserted into the fiber optic line.	self clear examine error counter for a history of this error.	Blink 1x once
773	Calibration Operation	3	This is not an error! Indicats number of automatic calibration cycles have been performed.	Self clear	none

Communication Failures					
#	Description	S	Remedy	How Cleared	Announced
1025	CMD Unknown Function A non-valid or non-implemented ModBus function was sent to the controller	1	Check your software for correct function calls.	self clear after one blink	Blink 1x once
1026	CMD Unknown Register A non implemented register address was addressed	1	Check your software for correct register addressing. See user manual with address table.	self clear after one blink	Blink 1x once
1027	CMD Wrong Register Count The register count in your command did not match the length of requested register.	1	Check your software for correct register addressing. See user manual with address table. ***Note:*** This controller does not allow to read across multiple registers.	self clear after one blink	Blink 1x once
1028	CMD Wrong Device Addr. The device address sent was not matching the address of this unit.	1	The MR330 controller has on fixed address at 235. If you are not sure what the address is talk to the unit at 235 and reset your desired bus address.	self clear after one blink	Blink 1x once
1029	CMD Wrong Value The data value was outside the permissible range for this parameter.	1	Consult the user instruction for the permissible parameter values allowed in each register.	self clear after one blink	Blink 1x once
1030	CMD Checksum ModBus Packet Checksum was invalid.	1	Resend the packet.	self clear after one blink	Blink 1x once

4.3.3 Reading The Error Counters

The entire packet of all 18 error counters may be read by issuing MODBUS command to Register 0x040 with a register count of 18. The sequence of registers is according to the error number in Table 1 in ascending order.

Each register is a 16-bit word. If the most significant bit is set to a logical one, this indicates that there is an active error residing in the Status stack.

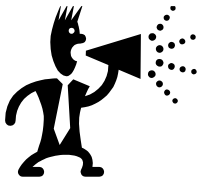
The remaining 15 bits indicate the number of errors that occurred since power was applied to the unit.

The user may clear all error counters by issuing Function Call FC5 coil #6.

5. Warranty Information

Warranty

MICRONOR INC. warrants this product to be free from defects in material and workmanship for a period of 1 (one) year from date of shipment. During the warranty period we will, at our option, either repair or replace any product that proves to be defective.



Applying improper supply voltage (5V ± 10%) voids warranty.

To exercise this warranty, write or call your local MICRONOR inc. representative, or contact MICRONOR INC. headquarters. You will be given prompt assistance and return instructions. Send the instrument, transportation prepaid, to the indicated service facility. Repairs will be made and the instrument returned transportation prepaid. Repaired products are warranted for the balance of the original warranty period, or at least 90 days.

Limitations of Warranty

This warranty does not apply to defects resulting from unauthorized modification or misuse of any product or part. This warranty also does not apply to Fiber Optic Connector interfaces, fuses or AC line cords. This warranty is in lieu of all other warranties, expressed or implied, including any implied warranty of merchantability of fitness for a particular use. MICRONOR INC. shall not be liable for any indirect, special or consequent damages.

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6. Specifications

6.1 MR302-2 OEM PCB Controller

Electrical Interface Description	 Specification
Connector	16-pin ribbon cable receptacle, 3M p/n N2516-5002-RB Recommended mating plug, 3M p/n 89116-0103
Quadrature Outputs	Quadrature A+/A-/B+/B- 5V RS422 Complementary Line Driver Bandwidth: 100 kHz maximum
Discrete Digital Signals	ZERO input, STATUS out (+5V TTL levels)
Digital Serial Interface	Modbus RTU, RS422/RS485 compatible User settable baudrate: 9,600 to 115,200
Power Supply	+5VDC ±5% , 80mA typical, 100mA maximum Recommended power supply: 5V/100mA

Optical Interface	Specification
Connectior	LC Duplex, PC Polish
Fiber Type	Duplex 62.5/125µm 0.275NA OM1 Multimode Fiber
Maximum Link Loss	Maximum 10dB round trip, 5dB one way
Operating Wavelength	850nm (for purposes of fiber link loss calculation)
Optical Output Power	< 0dBm (1mW) average (VCSEL diodes)
Laser Safety Classification	Class 1

Environmental & Mechanical	Specification
Temperature	-10°C to +65°C
Humidity	0% to 85% RH (non-condensing)
Ingress Protection	IP00 (none)
Mounting	4x #2-56 or M2.5 screws Mounting pattern 1.60" x 3.10 inches
Size	5.08 x 8.9cm (2.00 x 3.50")
Weight	25g (0.9oz)

Specifications subject to change without notice

6.2 MR303 Linear Sensor

Specifications for the sensor are listed for reference purposes only. Please consult separate data sheet for current information.

Position Measurement Description	Specification	Notes
Resolution	100µm	Dependent on film. Contact factory for specific requirements.
Maximum Speed	>100kHz	40m/sec

Optical Interface	Specification
Connectior	LC Duplex, PC Polish
Fiber Type	Duplex 62.5/125µm 0.275NA OM1 Multimode Fiber
Pigtail Length	1.5 to 10m
Maximum Link Loss	Consult Controller specifications

Physical		
Materials	Acetal, Ceramic, Glass	No ferromagnetic metals or conductive materials are used.
Dimension	30 x 28 x 15mm	1.18 x 1.10 x 0.59 inches
Weight	10g (0.3oz)	Without cable. Cable weight ~ 10g/m

Environmental	
Operating Temperature	-10° to +65°C
Storage Temeprature	-25° to +70°C
Humidity	0% to 95% RH, non-condensing
Ingress Protection	IP30 (keep free from contaminants)

Specifications subject to change without notice

6.3 MR304 Rotary Sensor

Specifications for the sensor are listed for reference purposes only. Please consult separate data sheet for current information.

Measurement - No Electronic Limitations Description	Specification	Notes
Resolution	256, 360, 512ppr	Pulses per revolution
Maximum RPM	25,000	Mechanical limit

Optical Interface	Specification
Connector	LC Duplex, PC Polish
Fiber Type	Duplex 62.5/125µm 0.275NA OM1 Multimode Fiber
Pigtail Length	1.5 to 10m
Maximum Link Loss	Consult Controller specifications

Physical		
Materials	Anodized aluminum housing Stainless steel shaft and bearings	
Dimension	Main Body, Ø24.9 x 38mm (Ø0.98 x 1.5 inches)	
Weight	50g (1.8oz)	With 3m pigtail Cable weight ~ 10g/m

Environmental		
Operating Temperature	-40° to +80°C	Continuous
Storage Temperature	-40° to +80°C	
Humidity	0% to 95% RH (non-condensing)	
Ingress Protection	IP40	

Specifications subject to change without notice

7. ZAPPY® 302 SOFTWARE

Micronor provides ZAPPY® 302 with the MR302-2 Controller Module. ZAPPY® for MR302 runs on: **Windows 8,** Windows 7, Vista, or XP with SP3 and with .net Framework 4.0 installed. Zappy® is used for diagnostics and troubleshooting in case the unit appears not to work properly. Zappy® is also useful for the engineer to become familiar with the controller board.

Note: The controller utilizes RS485/RS422 type signals not directly RS-232 compatible. A suitable signal translator is required.

If the PC has no Serial interface, a suitable USB to RS485/RS422 serial interface may be utilized. Sections 7.1 and 7.2 illustrate two examples using USB-to-RS422/485 Converter.

7.1 How To Install and Use Zappy® 302

1. Install ZAPPY® on your PC.
2. Start ZAPPY® and typically it will automatically find the MR302 PCB if properly connected to the serial interface.
3. ZAPPY® will open up to the System Functions screen as shown in Figure 8.

When parameter(s) are changed and you want to keep them saved in the PCB, you must click the "Set EEPROM" button.

Observe caution when changing serial interface parameters. The change will only take effect after a power-up boot. However, it is important that you remember what parameters were set, otherwise communication will no longer be possible with the unit.

7.2 ZAPPY® Menu Screens

7.2.1 System Functions screen

Figure 8 shows example of System Functions screen.

In this screen, the user can set Device Address, observe system status and error conditions.

When all parameter settings have been set (including User and Service Functions), the user should execute SET EPROM to update Controller operating parameters stored in EEPROM.

The Error Register log can be very helpful in determining when the controller board is not functioning properly.

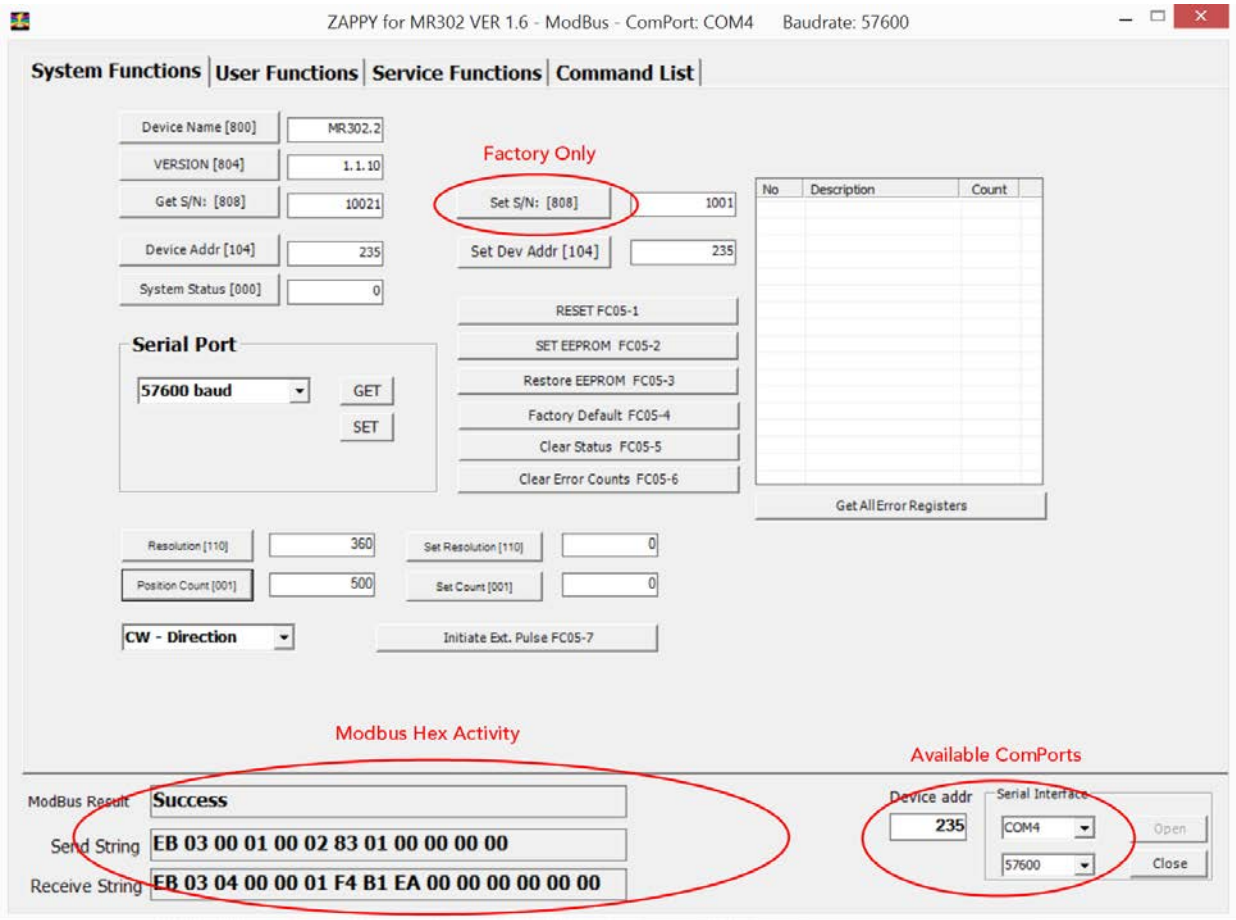


Figure 8. ZAPPY® System Functions screen

7.2.2 User Functions screen

Figure 9 shows example of User Functions screen.

In the User Functions screen, buttons are provided to read from and write to the various Controller registers. These buttons emulate the corresponding Modbus commands. Here, the user can actively operate the encoder system and oberve system status – Position Counter, Speed, etc.

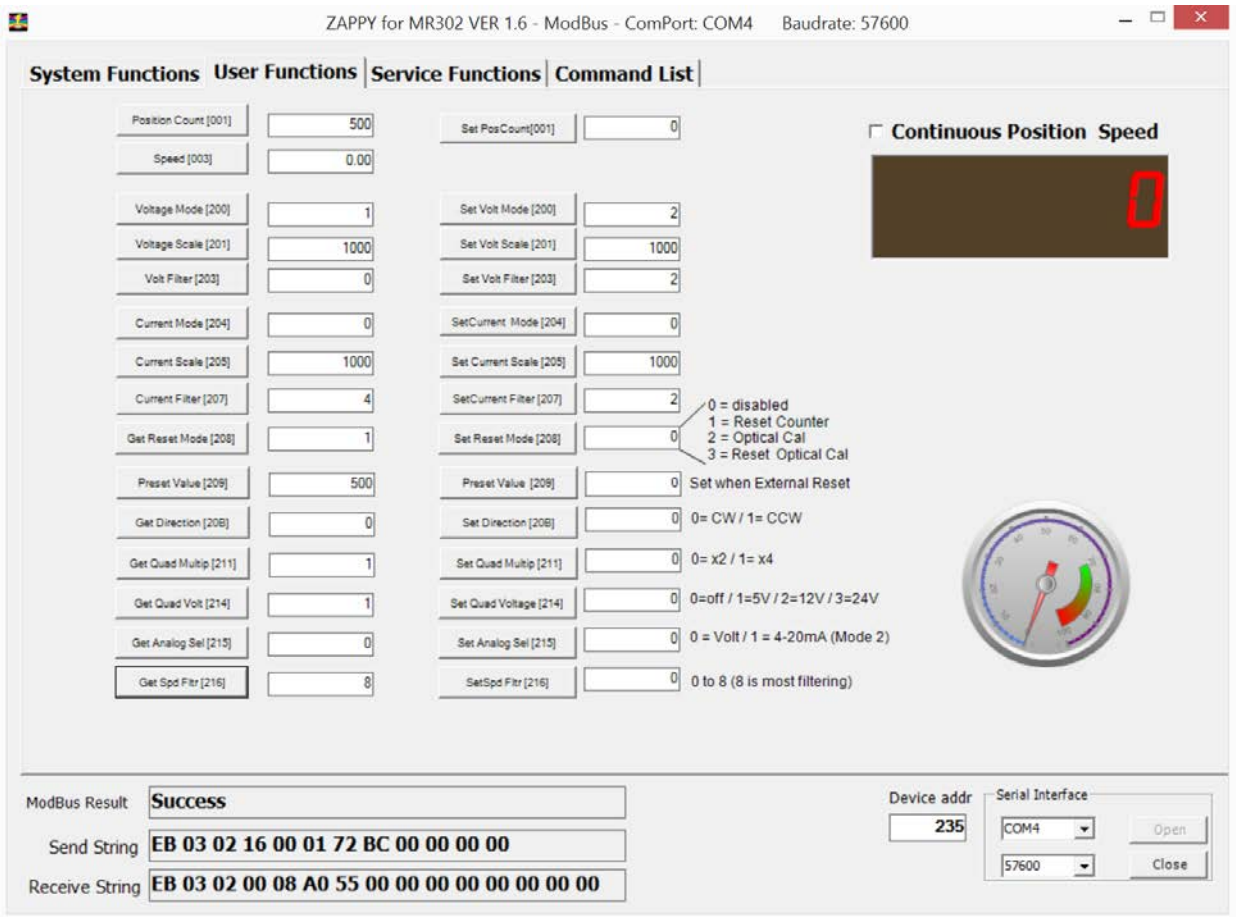


Figure 9. ZAPPY® User Functions screen

7.2.3 Service Functions screen

Figure 10 shows example of the Service Functions screen.

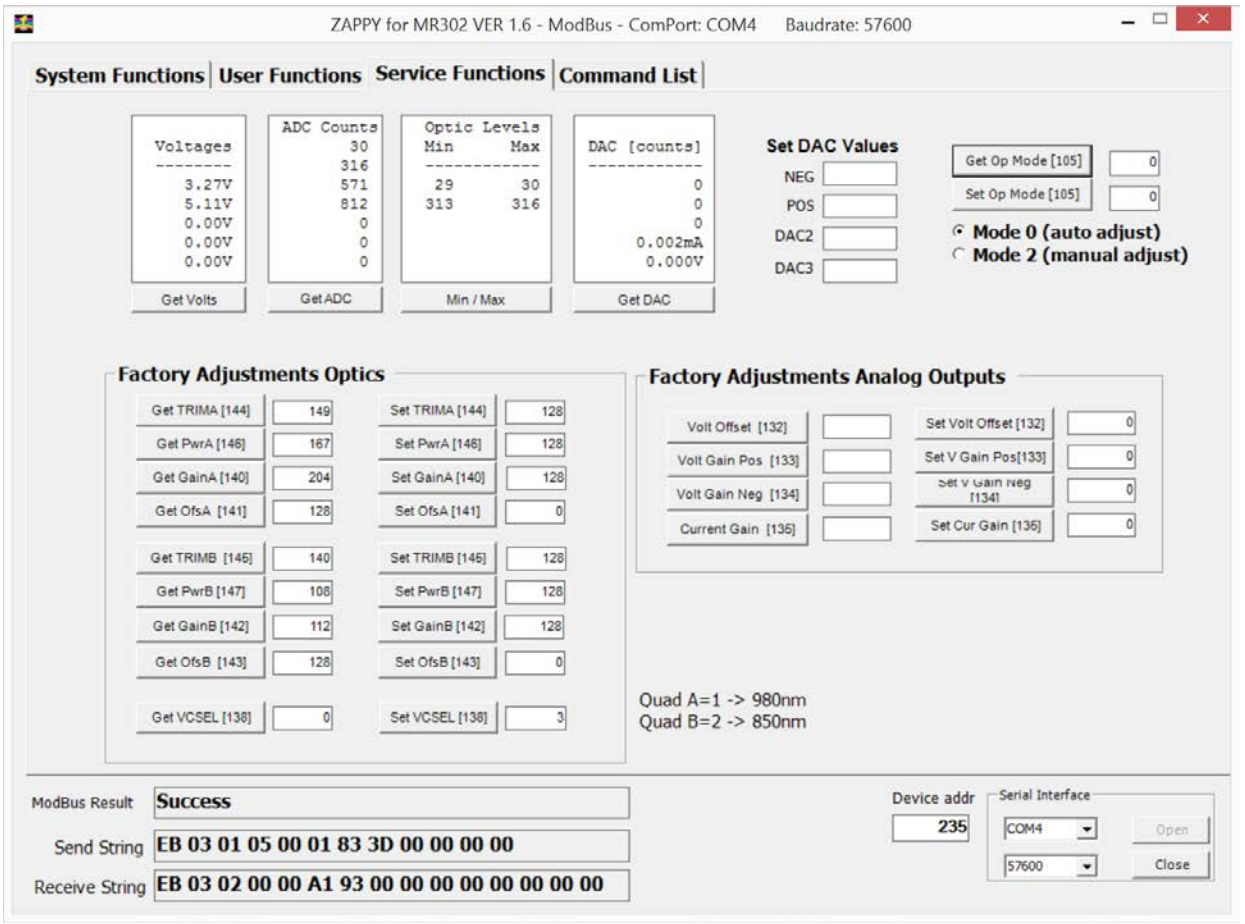
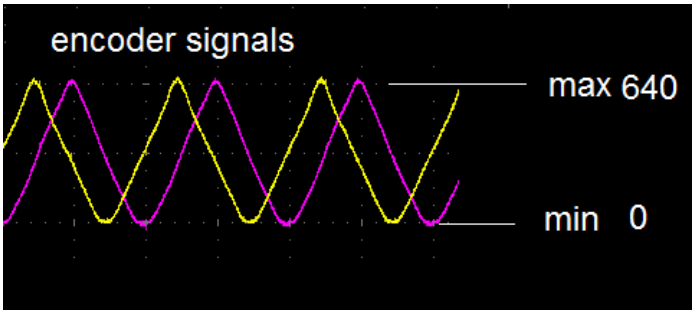


Figure 10. ZAPPY® Service Functions screen

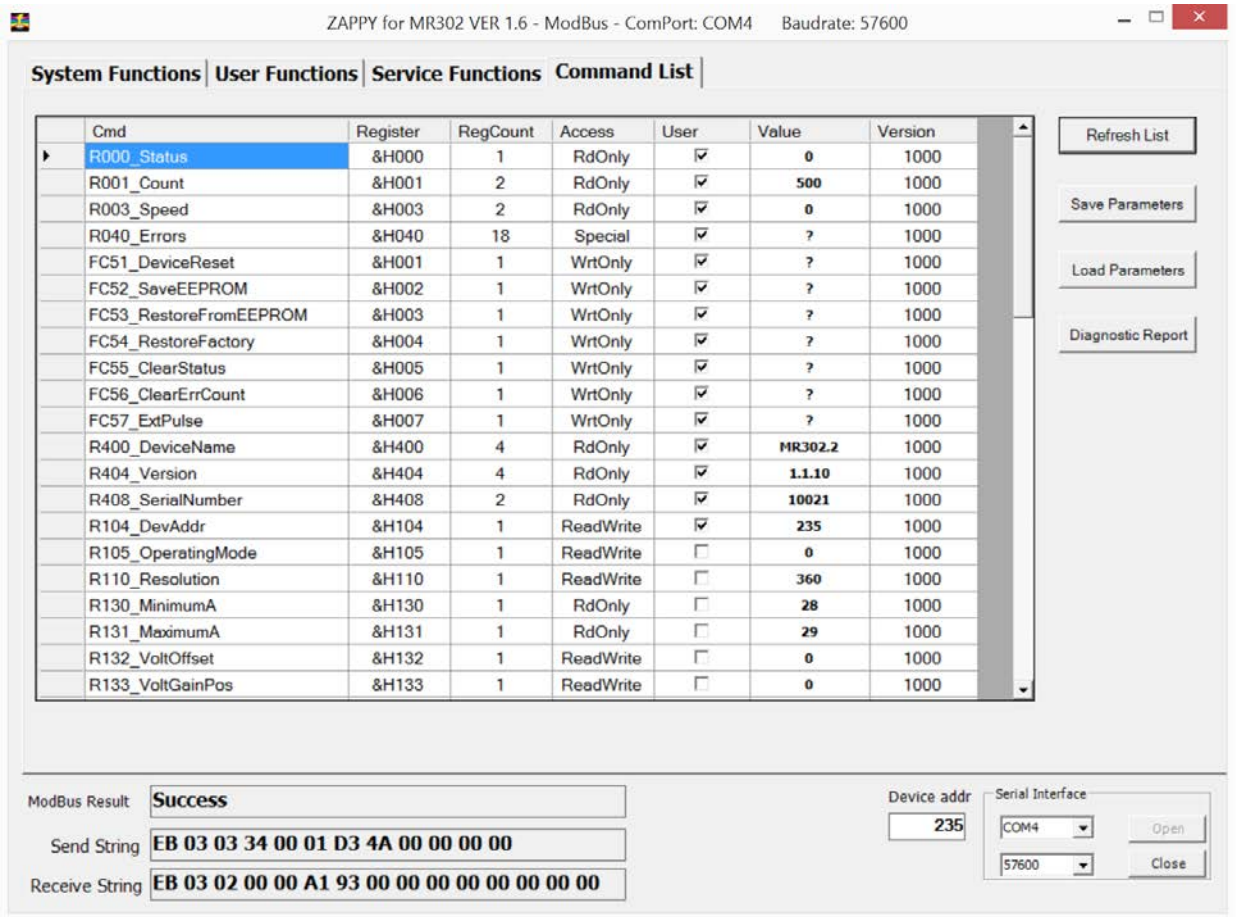
The Service Functions page allows the user to observe inner workings of the unit. "Get ADC" readings shows the user what the analog optical signal levels are.



The minimum and maximum voltage level for each channel are given. The built-in A/D converter is 10-bit and referenced to 3.3V. The voltage can be calculated V = 3.3V * (Count / 1024). Hence, 640 counts equals 2.06V. The peak level of the encoder signal is regulated to be 2V or 640 counts.

7.2.4 Command List screen

Figure 11 shows example of the Command List screen.



Cmd	Register	RegCount	Access	User	Value	Version
R000_Status	&H000	1	RdOnly	☑	0	1000
R001_Count	&H001	2	RdOnly	☑	500	1000
R003_Speed	&H003	2	RdOnly	☑	0	1000
R040_Errors	&H040	18	Special	☑	?	1000
FC51_DeviceReset	&H001	1	WrtOnly	☑	?	1000
FC52_SaveEEPROM	&H002	1	WrtOnly	☑	?	1000
FC53_RestoreFromEEPROM	&H003	1	WrtOnly	☑	?	1000
FC54_RestoreFactory	&H004	1	WrtOnly	☑	?	1000
FC55_ClearStatus	&H005	1	WrtOnly	☑	?	1000
FC56_ClearErrCount	&H006	1	WrtOnly	☑	?	1000
FC57_ExtPulse	&H007	1	WrtOnly	☑	?	1000
R400_DeviceName	&H400	4	RdOnly	☑	MR302.2	1000
R404_Version	&H404	4	RdOnly	☑	1.1.10	1000
R408_SerialNumber	&H408	2	RdOnly	☑	10021	1000
R104_DevAddr	&H104	1	ReadWrite	☑	235	1000
R105_OperatingMode	&H105	1	ReadWrite	☐	0	1000
R110_Resolution	&H110	1	ReadWrite	☐	360	1000
R130_MinimumA	&H130	1	RdOnly	☐	28	1000
R131_MaximumA	&H131	1	RdOnly	☐	29	1000
R132_VoltOffset	&H132	1	ReadWrite	☐	0	1000
R133_VoltGainPos	&H133	1	ReadWrite	☐	0	1000

Figure 11. ZAPPY® Command List screen

The Command List page lets the user see all the commands available and their settings programmed in the controller. This is helpful when writing interface software.

It also lets the user <save> and <load> given set of parameters so that all controllers can be programmed with the same set of parameters.

When discussing issues with the factory, it is recommended to save a Diagnostics Report file and send to the factory. This will speed up the trouble shooting process for the factory engineer.

When outputting a Dagnostics Report, please assure the encoder is running at some nominal speed.

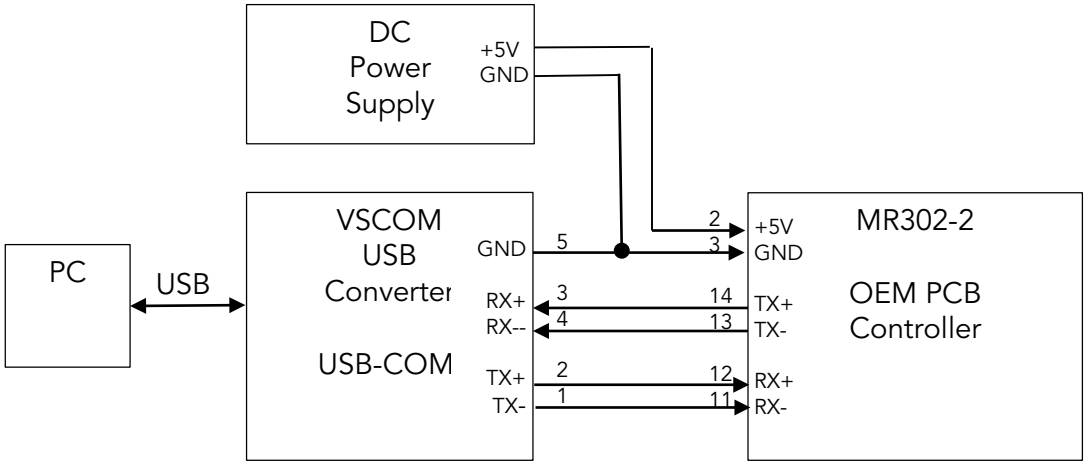
7.3 USB-to-RS422/485 Interface Examples

7.3.1 Full Duplex Modbus/RS485 Communications using USB Converter

For testing and demonstration purposes, the engineer can communicate with the MR302-2 Controller using a USB-to-RS422/485 converter operating in Full Duplex mode. This setup will also work with ZAPPY® 302 software running on a PC. A Half Duplex communications example is described in Section 7.3.2.

Materials Required:

- USB to RS422/485 Port Adapter, VScom P/N USB-COMi (www.vscom.de)
- 16C Ribbon Cable with 3M Ribbon Connector on one end
- DB9 Female Connector with Socket Contacts
- 5 VDC Power Supply



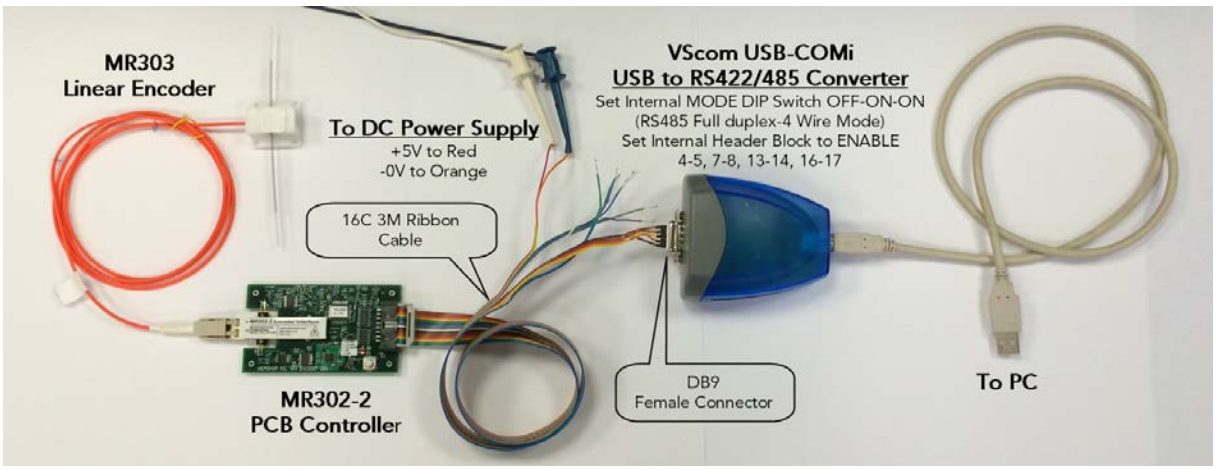
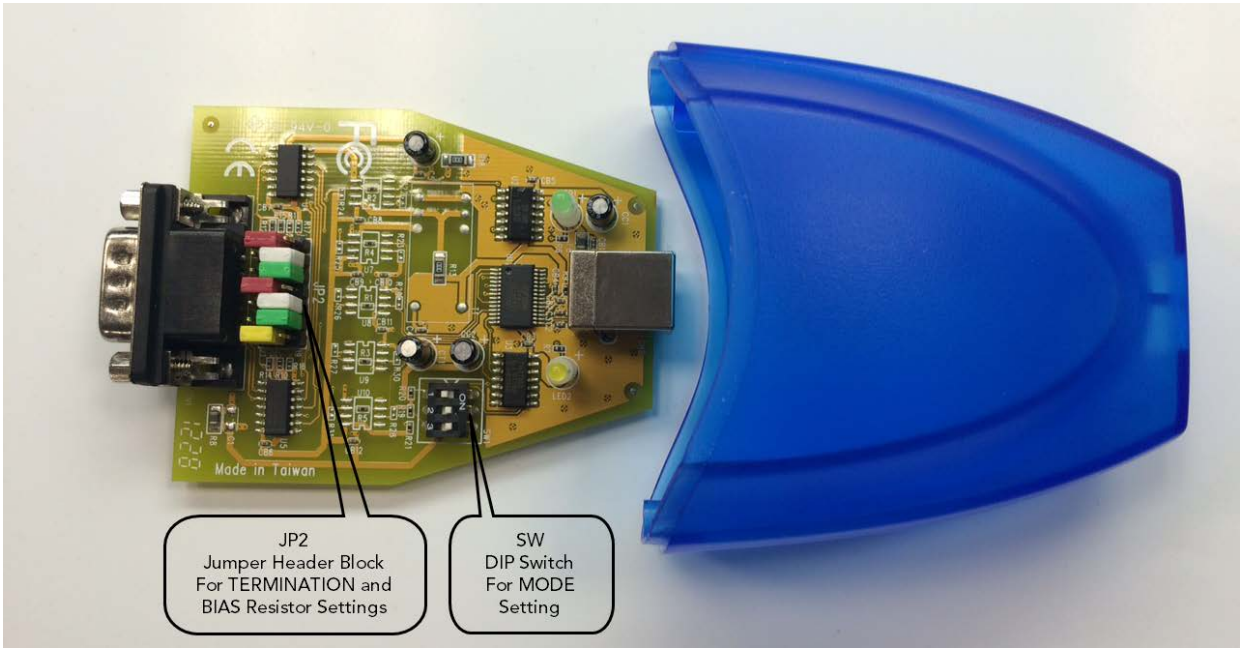


Figure 12. Full Duplex Test Setup using USB-to-RS485 Converter

MR302-2 J1 Pin#	Wire Color	Signal Function	USB-COMi DB9 Pin#	Signal Function
1	Brown	n/c		
2	Red	+5V		To Power Supply
3	Orange	GND		To Power Supply
4	Yellow	n/c		
5	Green	Encoder A-		
6	Blue	Encoder A+		
7	Purple	Encoder B-		
8	Grey	Encoder B+		
9	White	+5V		
10	Black	GND	5	GND
11	Brown	RCV-	1	XMT-
12	Red	RCV+	2	XMT+
13	Orange	TX-	4	RCV-
14	Yellow	TX+	3	RCV+
15	Green	Zero Input		
16	Blue	Status Out		

For this demonstation, the following USB-COMi internal settings are required and are as shown in the photograph below:

1. Set SW MODE DIP switch to RS485 Full Duplex (4-Wire) Mode:
    - S1-S2-S3: OFF ON ON
2. Set JP2 LINE RESISTORS to Pull-Up/Pull-Down Biasing Mode:
    - DISABLE Jumpers: 2-3, 11-12, 20-21
    - ENABLE Jumpers: 4-5, 7-8, 12-14, 16-17



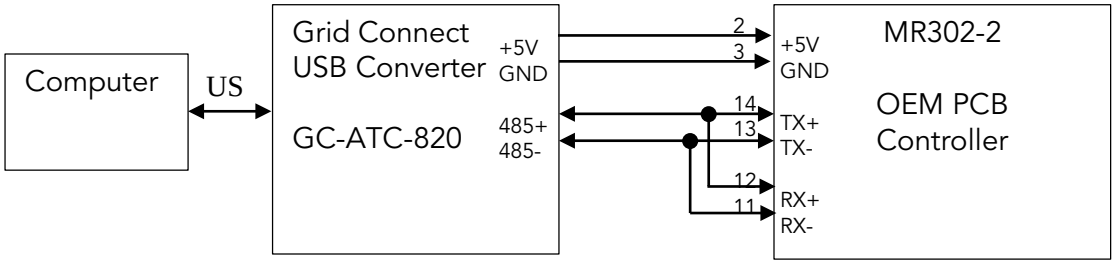
7.3.2 Half Duplex Modbus/RS485 Communications using USB Converter

For testing and demonstration purposes, the MR302-2 PCB can be connected to a PC using the USB interface and USB power. This example demonstrates Half Duplex communications.

Materials Required:

- USB to RS485 Adapter, GridConnect P/N GC-ATC-820 (www.gridconnect.com)
- 16C Ribbon Cable with 3M Ribbon Connector on one end
- DB9 Female Connector with Socket Contacts

Note: This example also shows the GC-ATC-820 powering the MR302-2 Controller from the USB. Consult Section 7.3.3 on how to internally connect the USB +5V output to the DB9 connector interface.



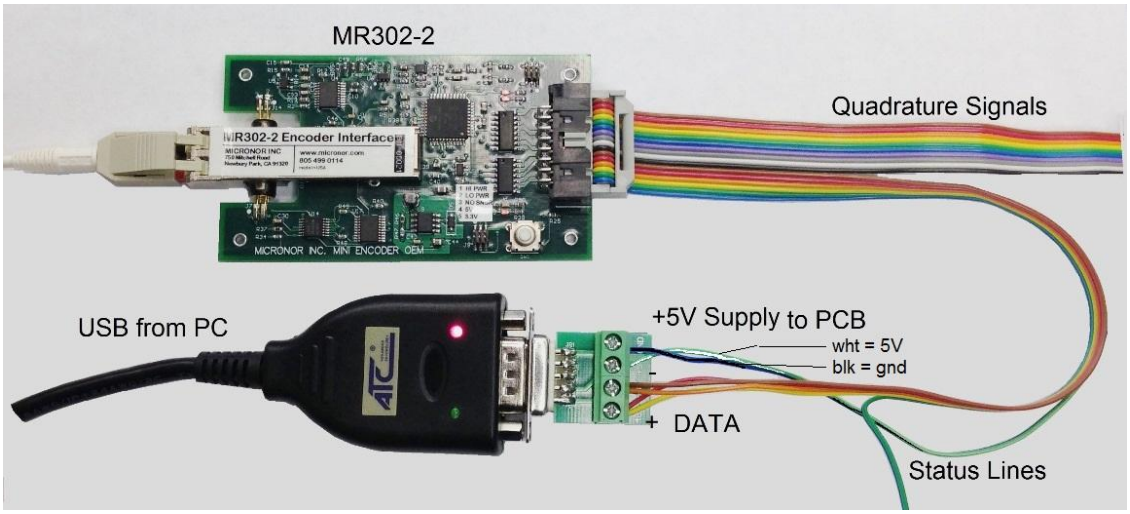
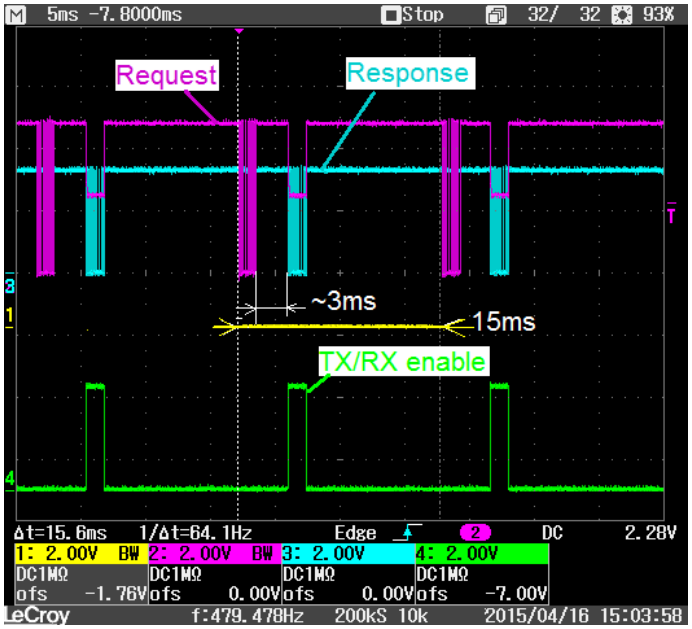


Figure 13. Half Duplex Test Setup using USB-to-RS485 Converter

MR302-2 J1 Pin#	Wire Color	Signal Function	GridConnect Pin#	Signal Function
1	Brown	n/c		
2	Red	+5V		To Power Supply
3	Orange	GND		To Power Supply
4	Yellow	n/c		
5	Green	Encoder A-		
6	Blue	Encoder A+		
7	Purple	Encoder B-		
8	Grey	Encoder B+		
9	White	+5V	3	+5V Out
10	Black	GND	4	GND
11	Brown	RCV-	2	485-
12	Red	RCV+	1	485+
13	Orange	TX-	2	485-
14	Yellow	TX+	1	485+
15	Green	Zero Input		
16	Blue	Status Out		

ModBus Communication Timing

ModBus protocol requires the Master to query an individual node by sending a device address command or request. Only the addressed device may respond.
The MR302-2 device typically responds within 3ms or after a valid request / command has been received. At 57600 baud, it is possible to read out the position counter at a rate of 10ms. In a bussed environment, device 1, 2, 3, 4, ... n may be addressed at that same rate so as not to cause a bus conflict.



This actual scope picture shows the unit responding within 3ms upon receiving a valid request. The maximum latency uncertainty varies within 1.5ms
The device is always in listening mode unless when it is transmitting. The purple trace shows clearly when the receive channel is disabled while the unit is transmitting a response, blue trace.

ModBus Multiple Units on Bus

Each ModBus node (MR302-2) must have a unique device address.
The MR302-2 controllers are pre-programmed with the address 235 (hex 0xEB)

The address 235 (hex 0xEB) is the common call address. The unit will always respond to this address. Do not use when multiple units are connected on a bus.

When bussing several units together, each controller must first be assigned a unique bus address.

Connect one unit only and set the desired bus address for each controller. ZAPPY® software may be used for that purpose. Make sure to save the changed address to EEPROM before disconnecting from power.

Example:
Three MR302-2 Controllers have been bused together as shown below. The boards have been given addresses 230, 231, 232.

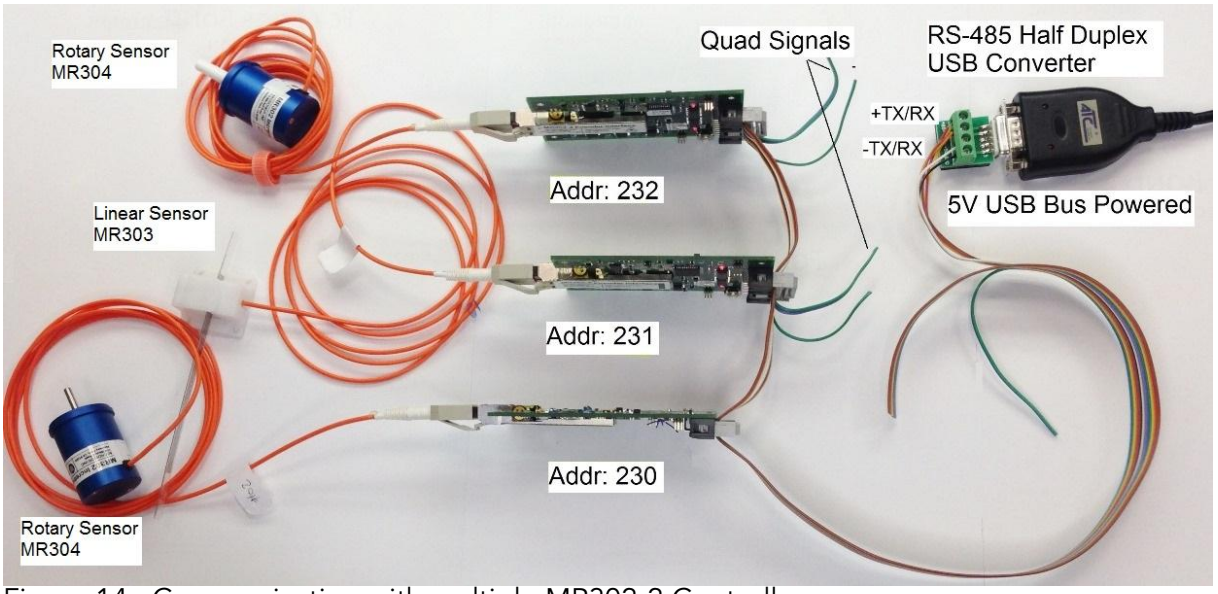


Figure 14. Communicating with multiple MR302-2 Controllers

The bus can be elegantly implemented using the ribbon cable. However, make sure the non-bus signals such as the quadrature encoder outputs and the status output are isolated as shown in the picture above.

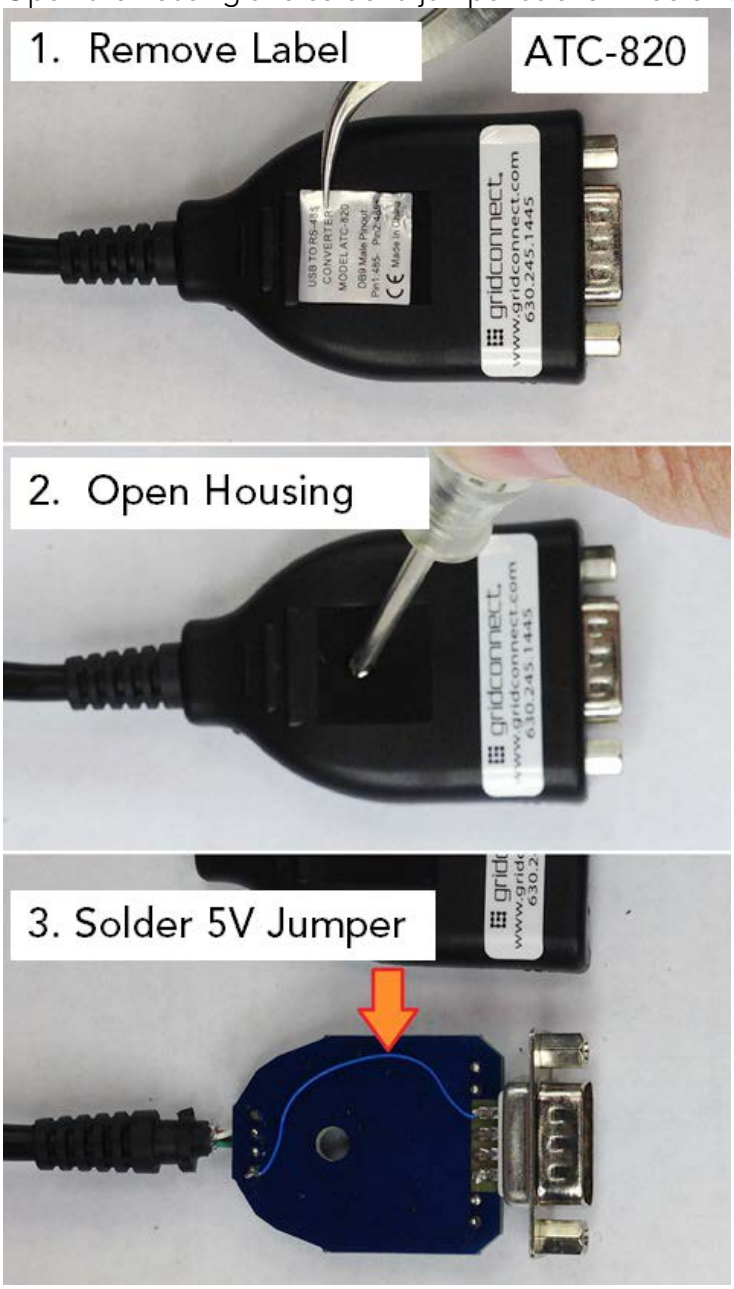
Each board can now be polled as part of the Modbus system.
In this example the controller polls one board every 15ms. The update rate for each individual motion axis is 45ms.

7.3.3 How To Power MR302-2 Controller from USB

For testing and demonstration purposes, the MR302-2 PCB Controller can be powered from a USB interface. This section shows how to make the internal connection to the Grid Connect GC-ATC-820 converter used in the Half Duplex demonstration described in the previous Section 7.3.2.

Modification to GC-ATC-820 Converter to output +5V. The interface cable comes without the USB +5V connection.

Open the housing and solder a jumper as shown below.



8. MR302 Theory of Operation

In this section, we explain the inner workings of the MR30X incremental encoder system.

8.1 MR302-2 PCB Controller

The system incorporates an all-optical design per Micronor's US Patent 7,196,320. There are no electronics in the sensor whatsoever.

The controller sends light of two distinct different colors through the transmit fiber. Within the sensor the two colors are split up into two distinct collimated light beams. Each beam passes through a spatial filter probing the A and he B track on the sensor wheel. The light of each beam is now modulated with the 90° phase shift based on the turning direction of sensor wheel. The modulated light is coupled back into the optical receive fiber guiding the light back to the receiver in the controller module.

The two colors of light are returned to the controller, converted back into an electrical signal, amplified to a known level, and then output as A/B quadrature signals.

Fiber optics will guide the light efficiently and over large distances. However the light amplitude is not guaranteed to stay stable at all. The microprocessor main role is to supervise the optical power levels and make the necessary adjustments when the light levels drift.

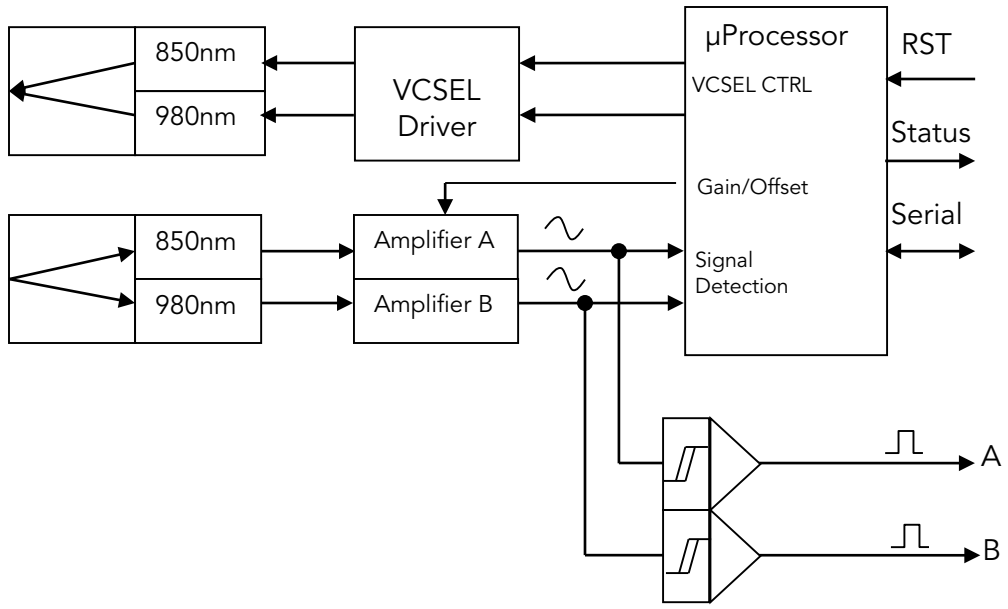
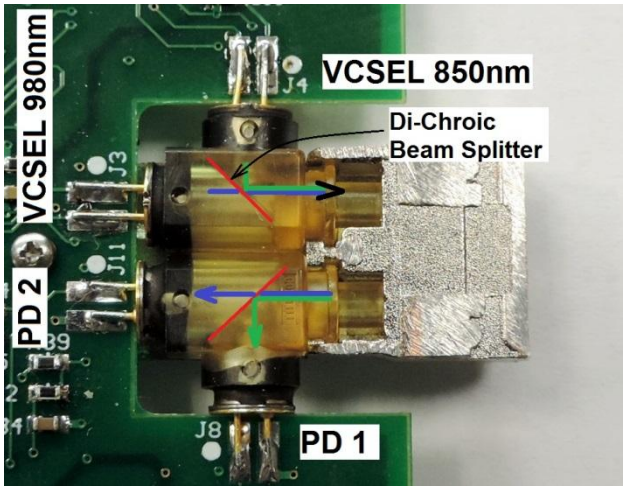


Figure 15. Block Diagram of MR302-2 Controller

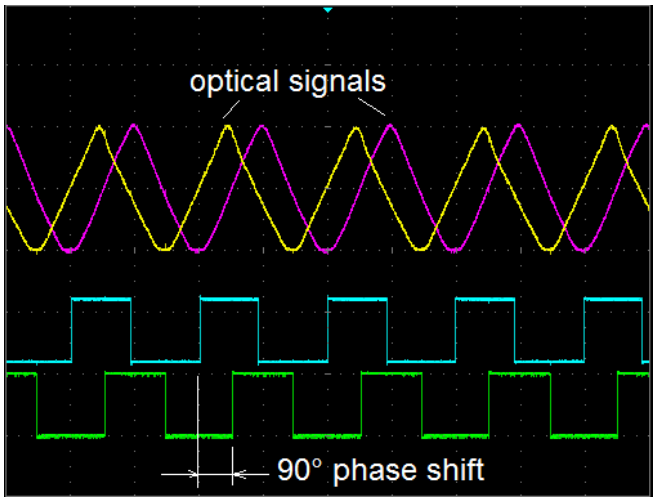
Two light beams are generated by two VCSEL diodes, emitting at 850nm and 980nm. The light of the two VCSEL diodes is combined using an optical dichroic beam splitter. The two wavelengths are guided by the optical fiber as parallel information.



Since VCSEL (Vertical Cavity Surface Emitting Laser) diodes are indeed laser diodes, they must be electronically stabilized. In the block diagram, this is depicted within the "VCSEL Driver" block. A small portion of the emitted light is measured with an integral photodiode. The photodiode current is stabilized to a constant value. Thus, a constant optical output is maintained.

The micro controller has full control over the ON/OFF state and the power level of the VCSEL diodes. During manufacturing, the optical power level is calibrated to the desired value. Within ZAPPY® software this level is accessible via Modbus commands 0x144 and 0x145.

The receiver is comprised of a dichroic beam splitter which separates the two wavelengths. The light of each wavelength is converted into an electrical current by photo diode 1 and photo diode 2.



The sensor modulates the light accurately. The scope picture shows the optical analog signal following a triangular shape as the encoder disk is blocking the beam gradually.

The lower two scope traces show the quadrature output after passing through the Schmitt trigger circuit.

The microprocessor main function is to supervise the incoming optical signal, regulate the amplitude and perform other plausibility tests. Based on these tests status codes of various types are generated.